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Wiggins et al.

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(45) **Date of Patent: Jan. 24, 2017**

(54) **UNDERWATER VEHICLE CUTTING APPARATUS**

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Related U.S. Application Data

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(60) Provisional application No. 61/445,847, filed on Feb. 23, 2011.

(51) **Int. Cl.**

B63G 8/28	(2006.01)
B63C 11/52	(2006.01)
B63G 9/00	(2006.01)
B26D 1/00	(2006.01)
B26D 1/11	(2006.01)
B63G 7/00	(2006.01)
B63G 8/00	(2006.01)

(52) **U.S. Cl.**
CPC ***B63C 11/52*** (2013.01); ***B26D 1/0006*** (2013.01); ***B26D 1/11*** (2013.01); ***B63G 8/001*** (2013.01); ***B63G 9/00*** (2013.01); *B26D 2001/006* (2013.01); *B26D 2001/0066* (2013.01); *B63G 2007/005* (2013.01); *B63G 2008/002* (2013.01); *Y10T 83/04* (2015.04); *Y10T 83/6935* (2015.04)

(58) **Field of Classification Search**
CPC B63G 8/29; B63G 7/04; B63G 8/28
USPC .. 114/221 A, 20.3, 221 R; 30/169, 392, 393, 30/209, 173, 180, 182, 216, 228; 83/751, 759; 56/236, 237
See application file for complete search history.

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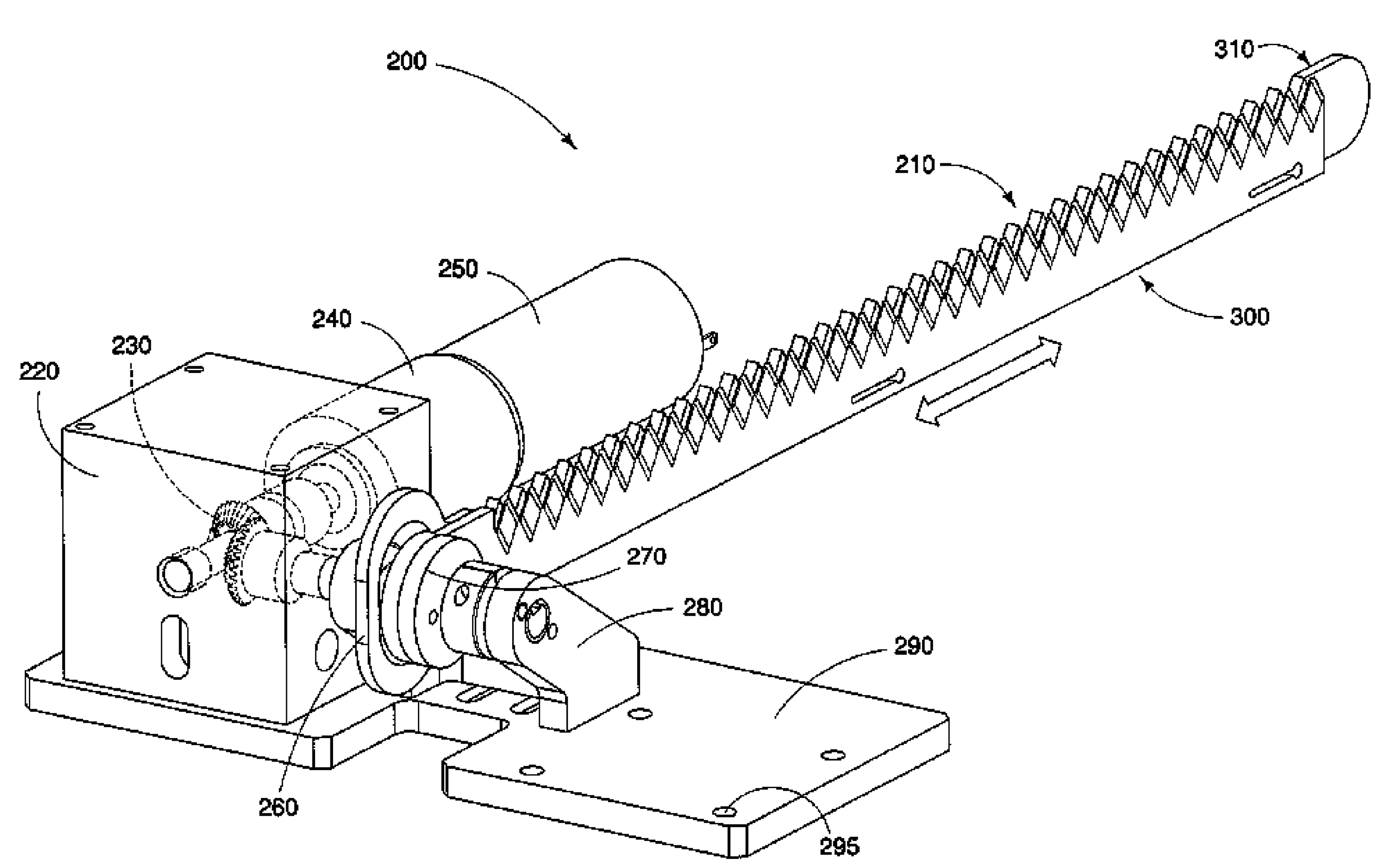
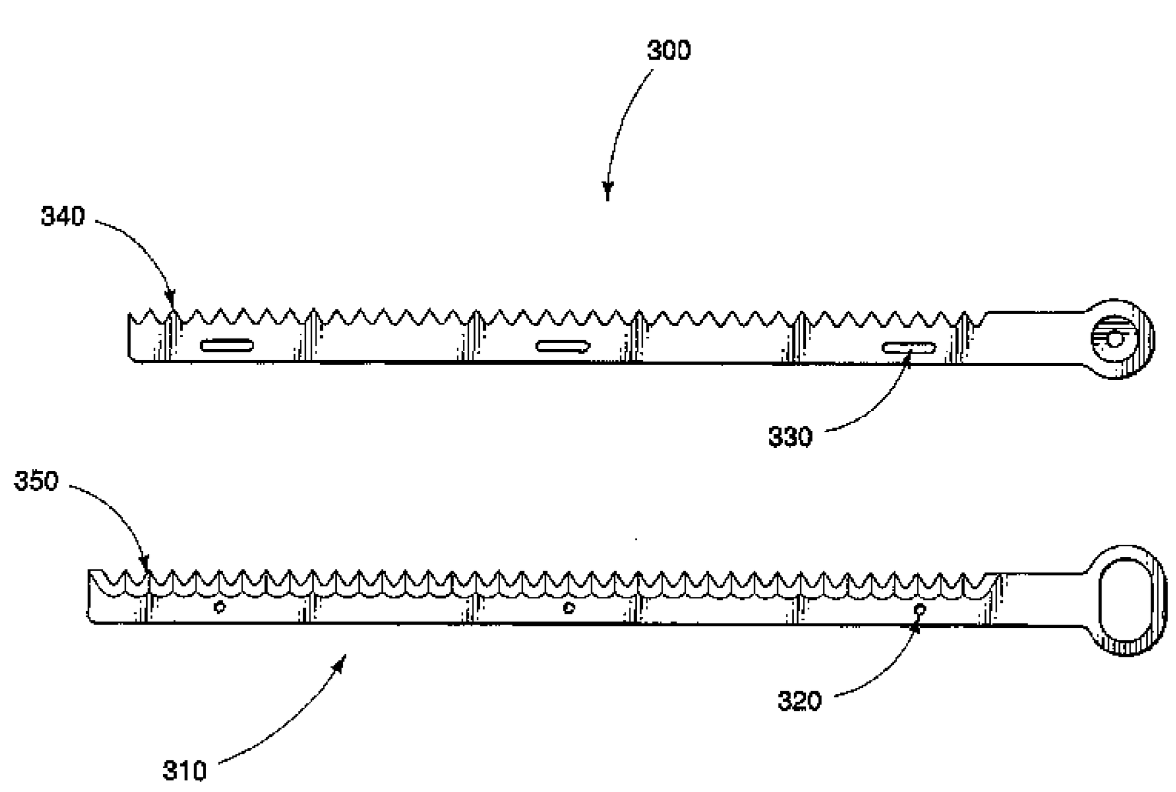
(57) **ABSTRACT**

The problem of penetrating through nets and other objects is solved by cutting the object using a linear cutting assembly having a linear cutter arm that moves in an arc and pivots about an attachment point. The object is cut by a severing action caused by a moveable blade of the linear cutting arm moving back and forth across a stationary blade of the linear cutter arm. An underwater vehicle modified to incorporate an embodiment of the linear cutting assembly can cut a sufficiently large opening in the object to allow the vehicle to pass through.

18 Claims, 22 Drawing Sheets





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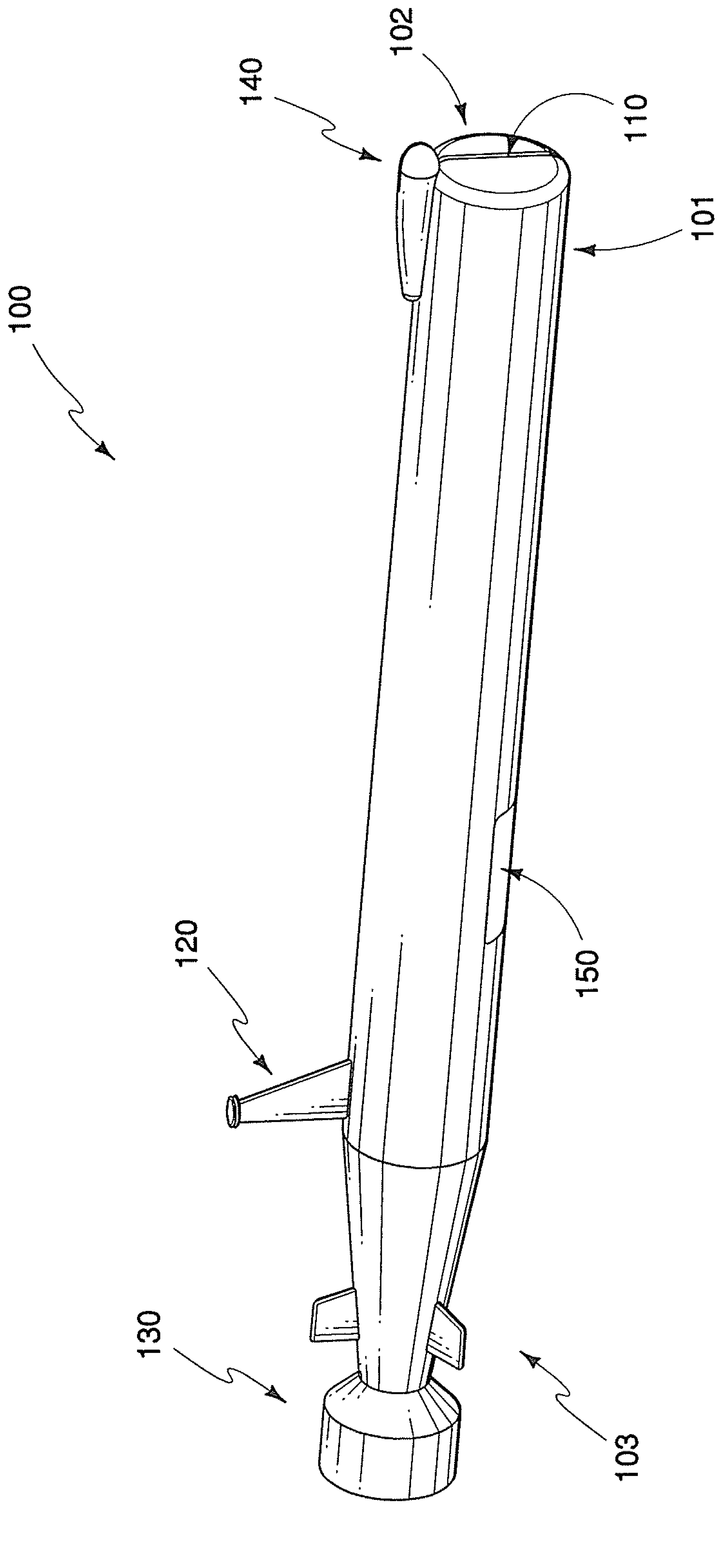


FIG. 1

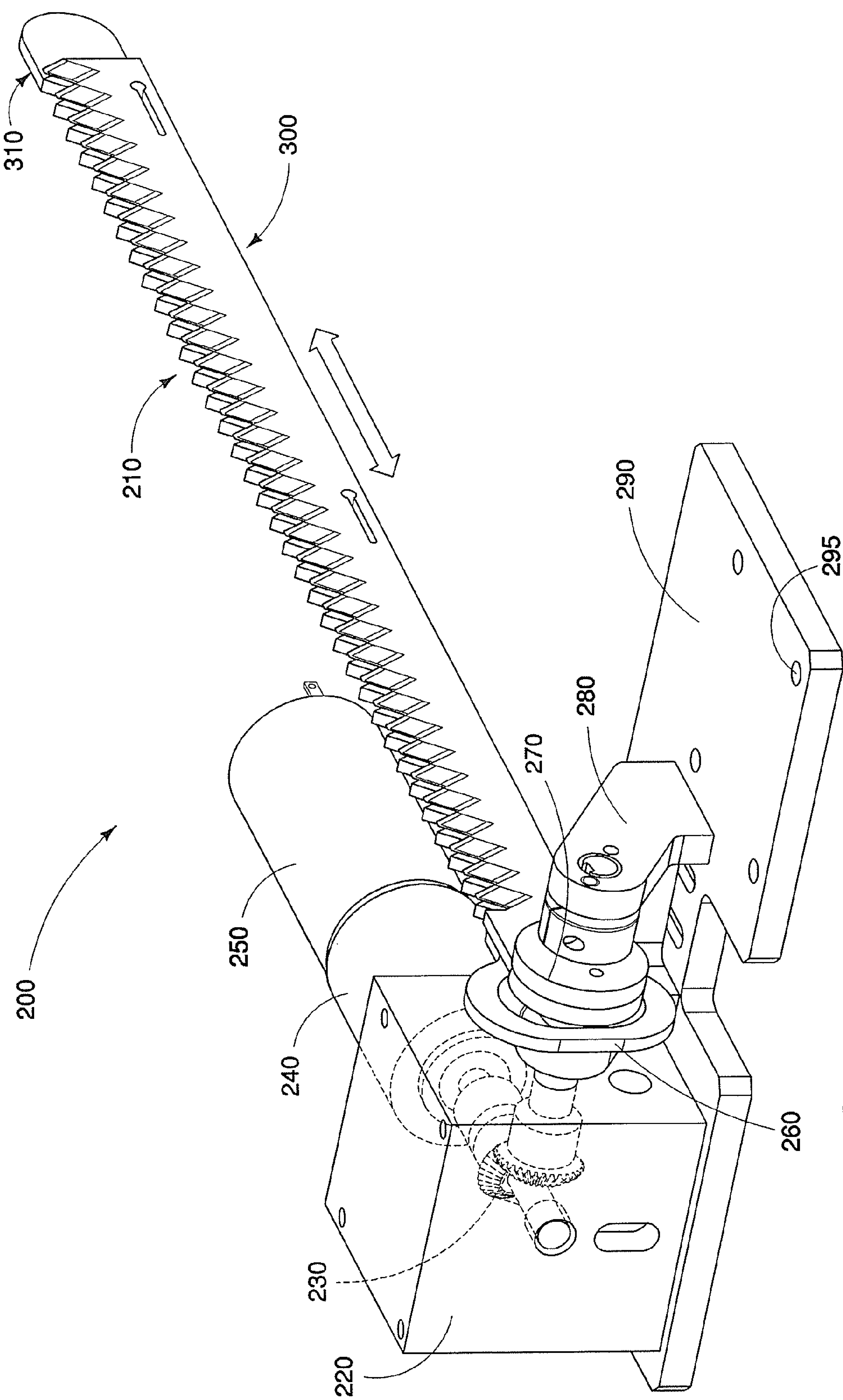


FIG. 2

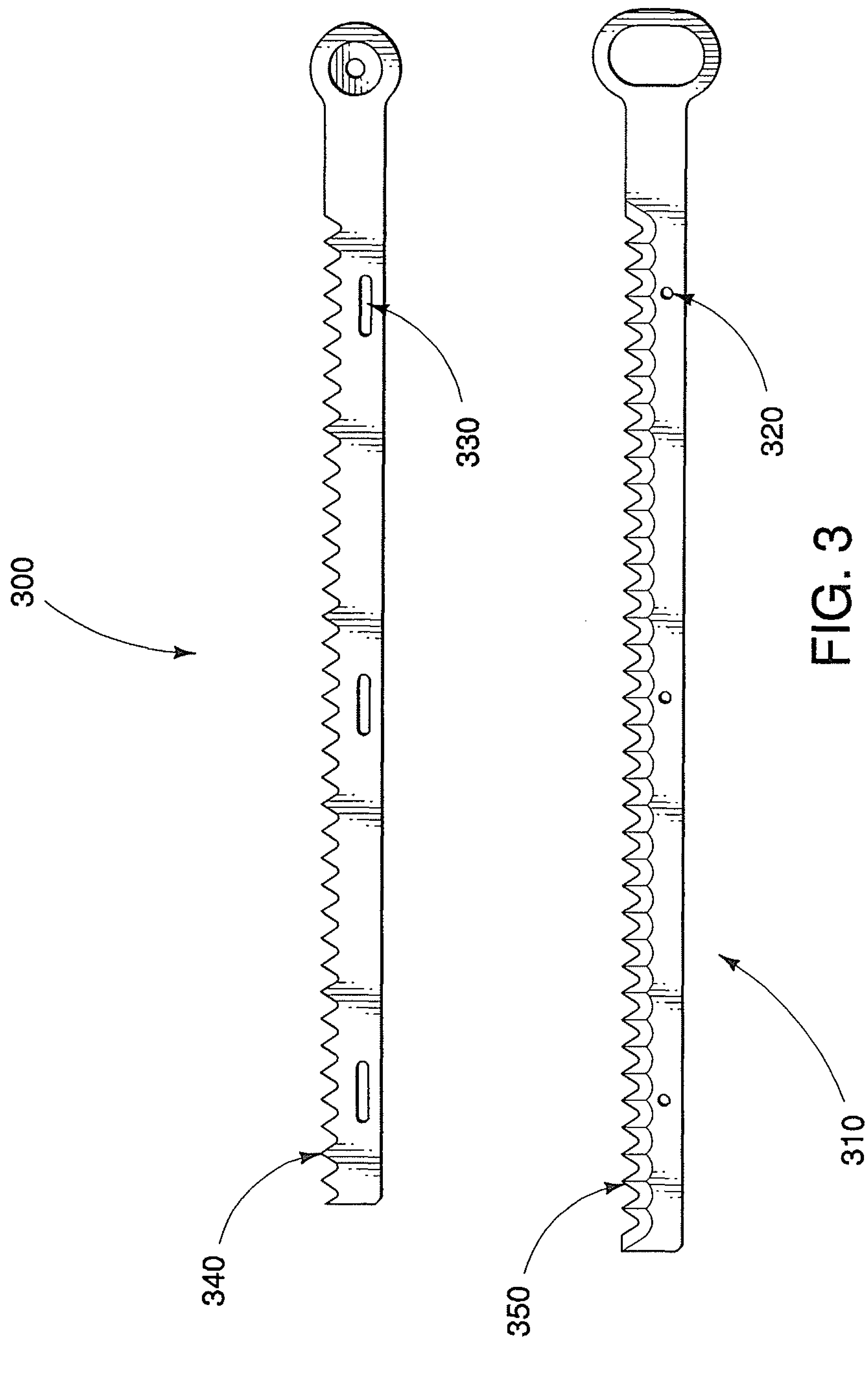


FIG. 3

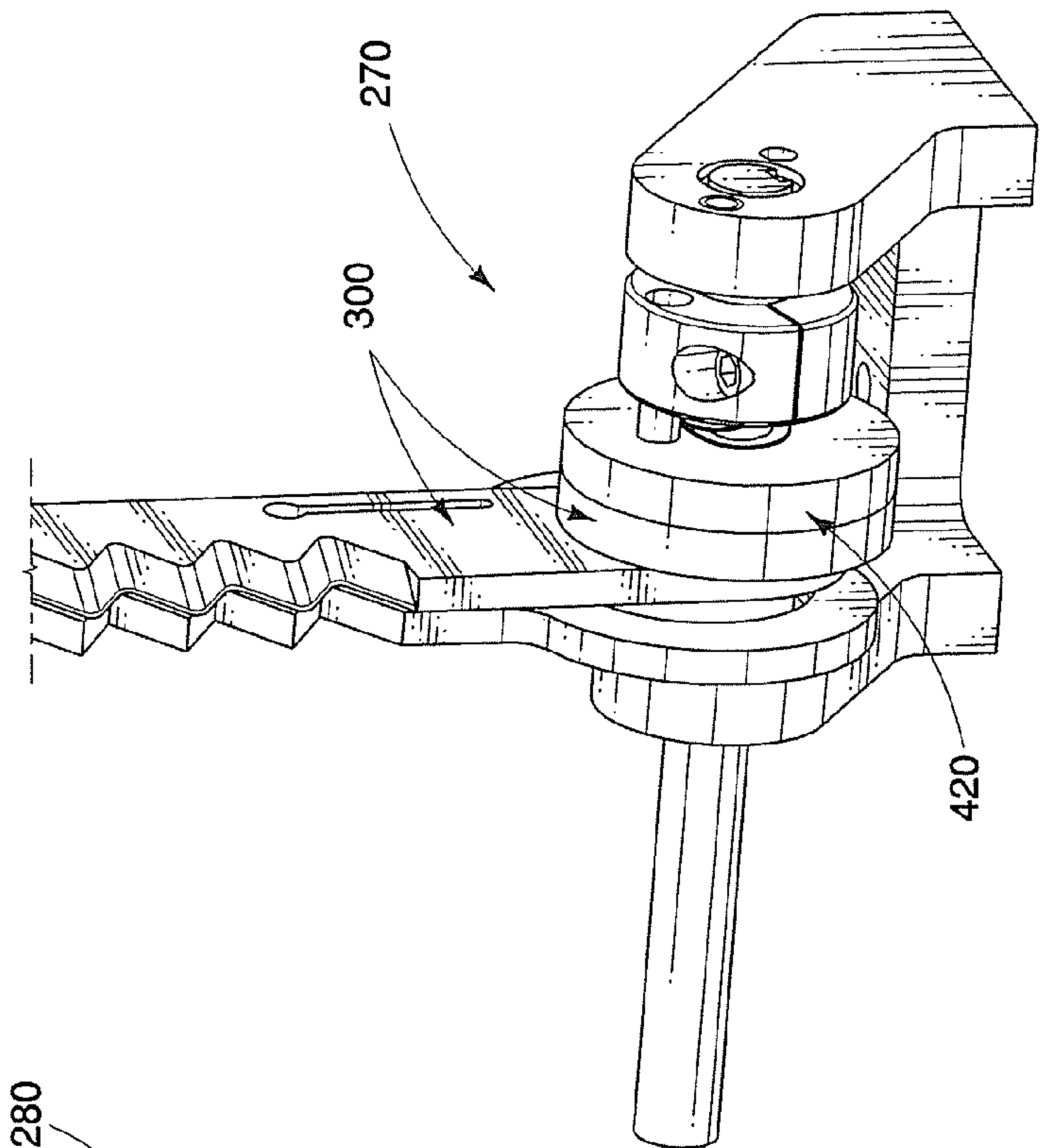


FIG. 4B

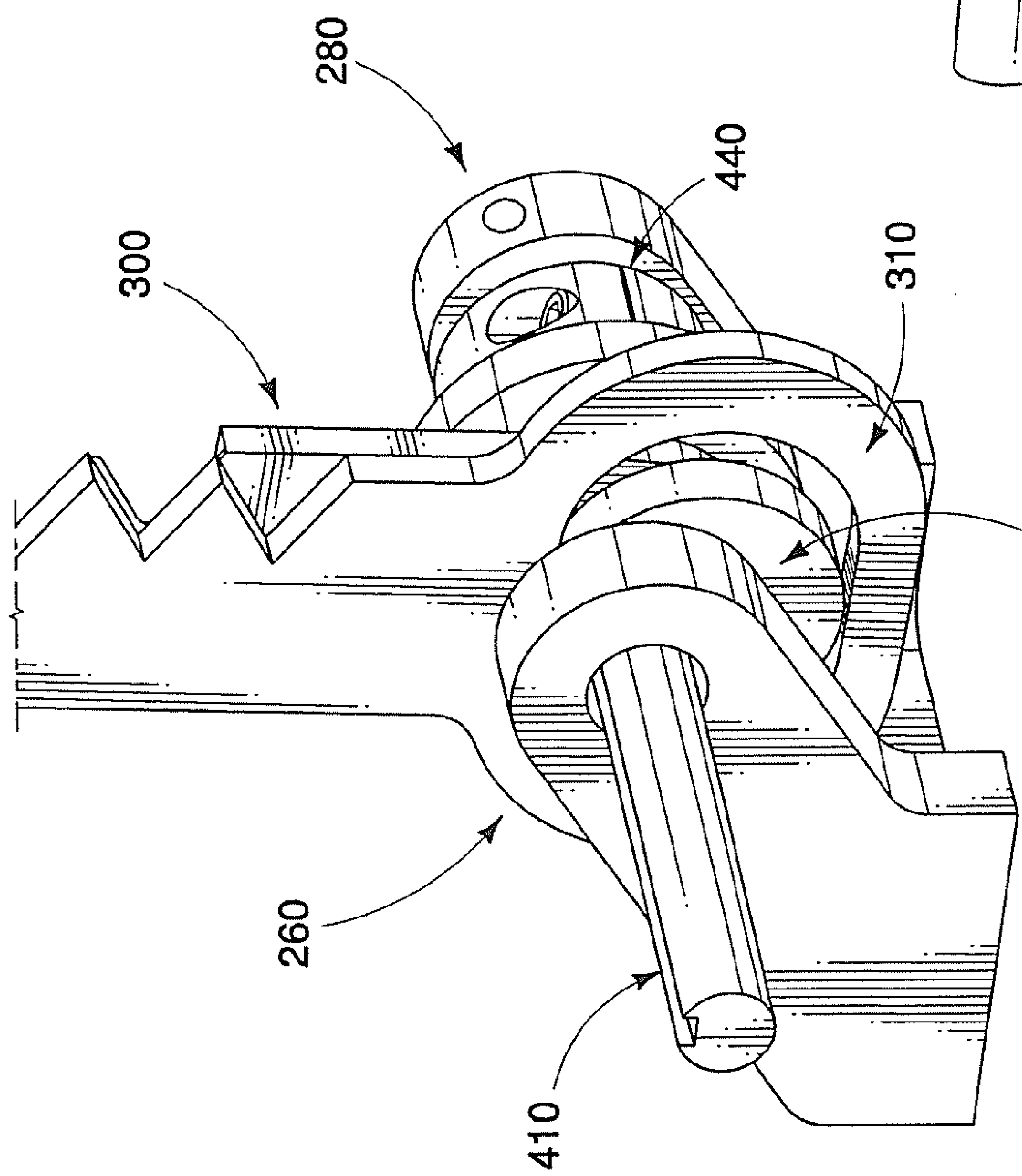


FIG. 4A

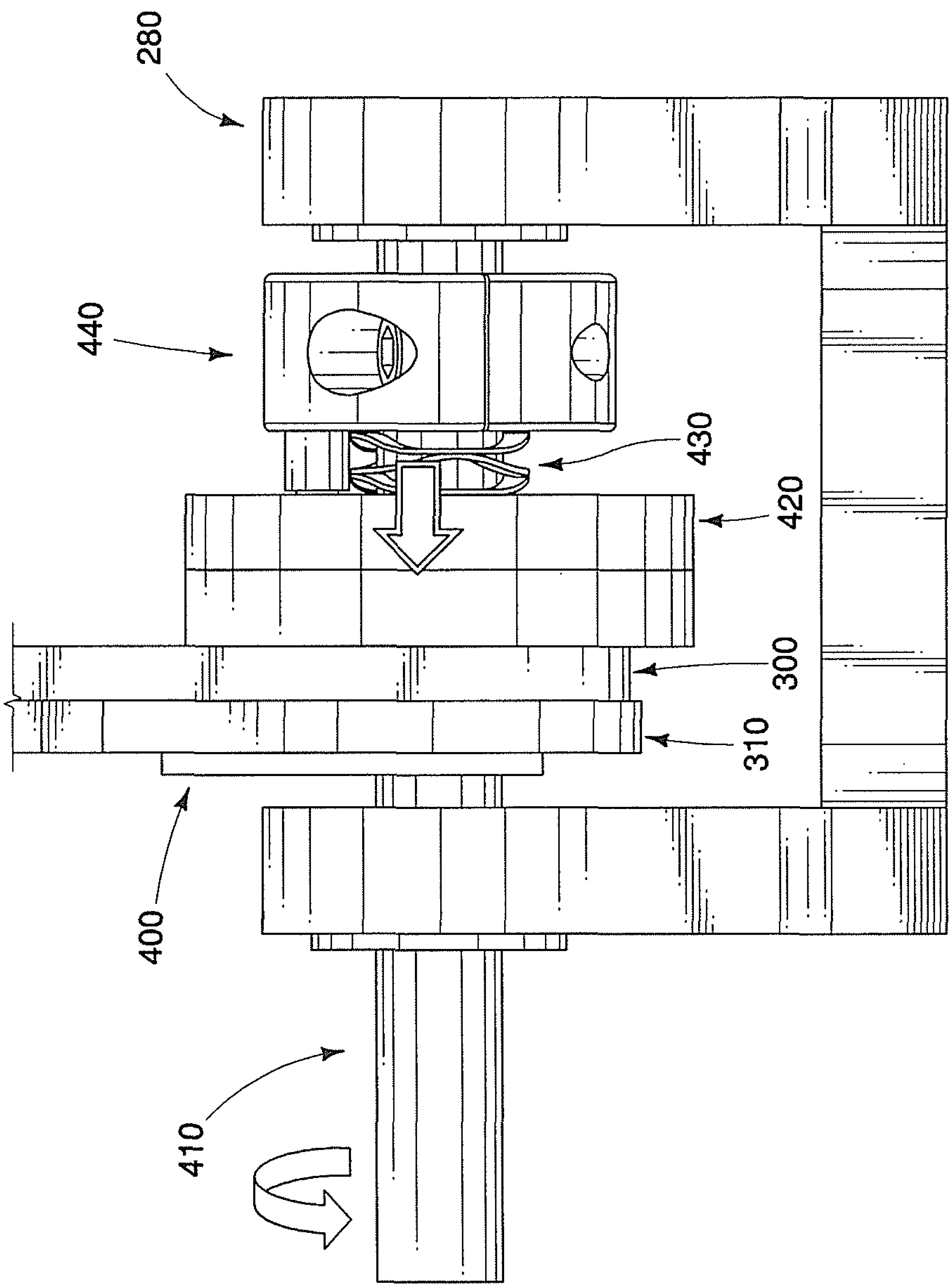


FIG. 4C

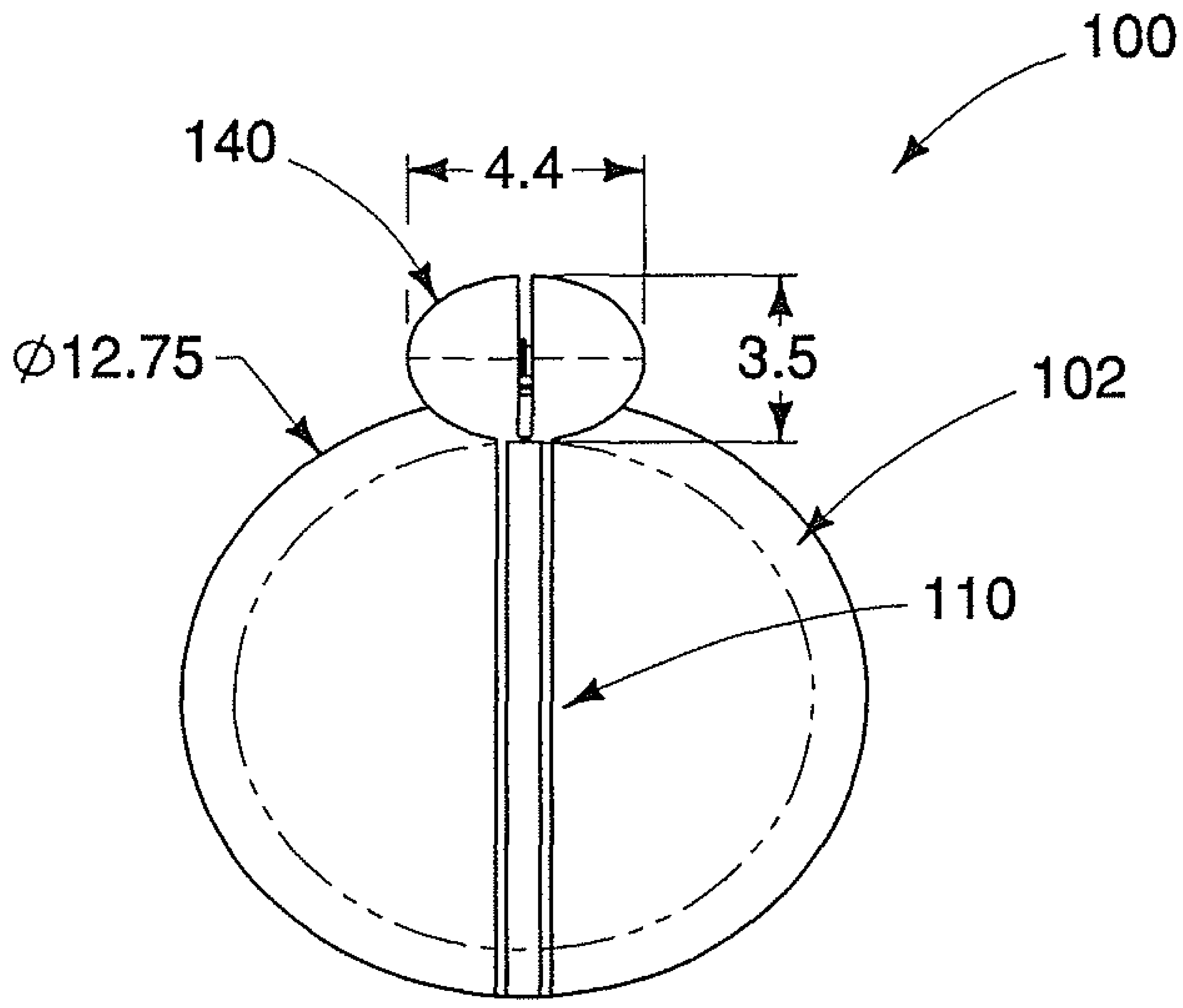


FIG. 5A

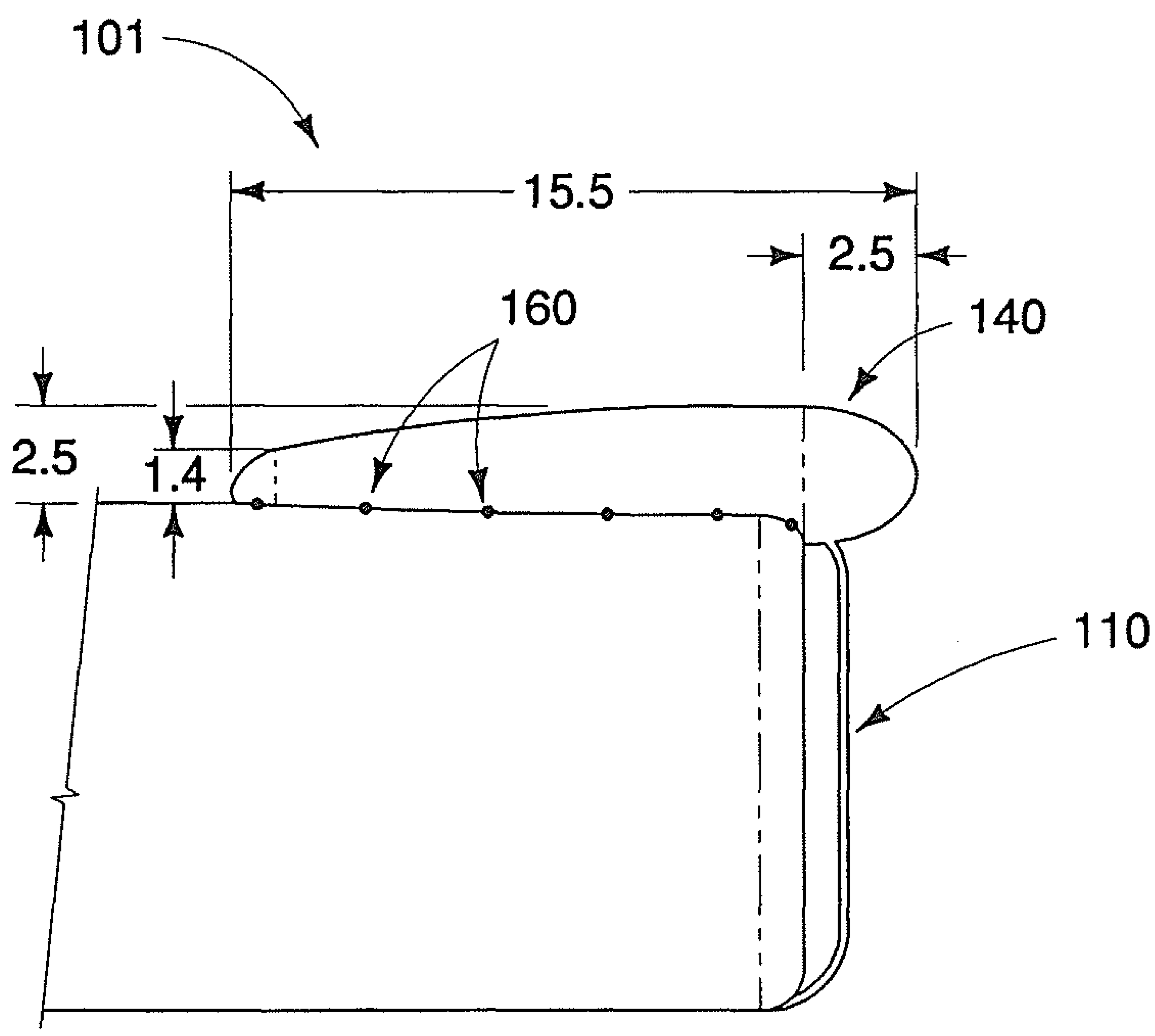
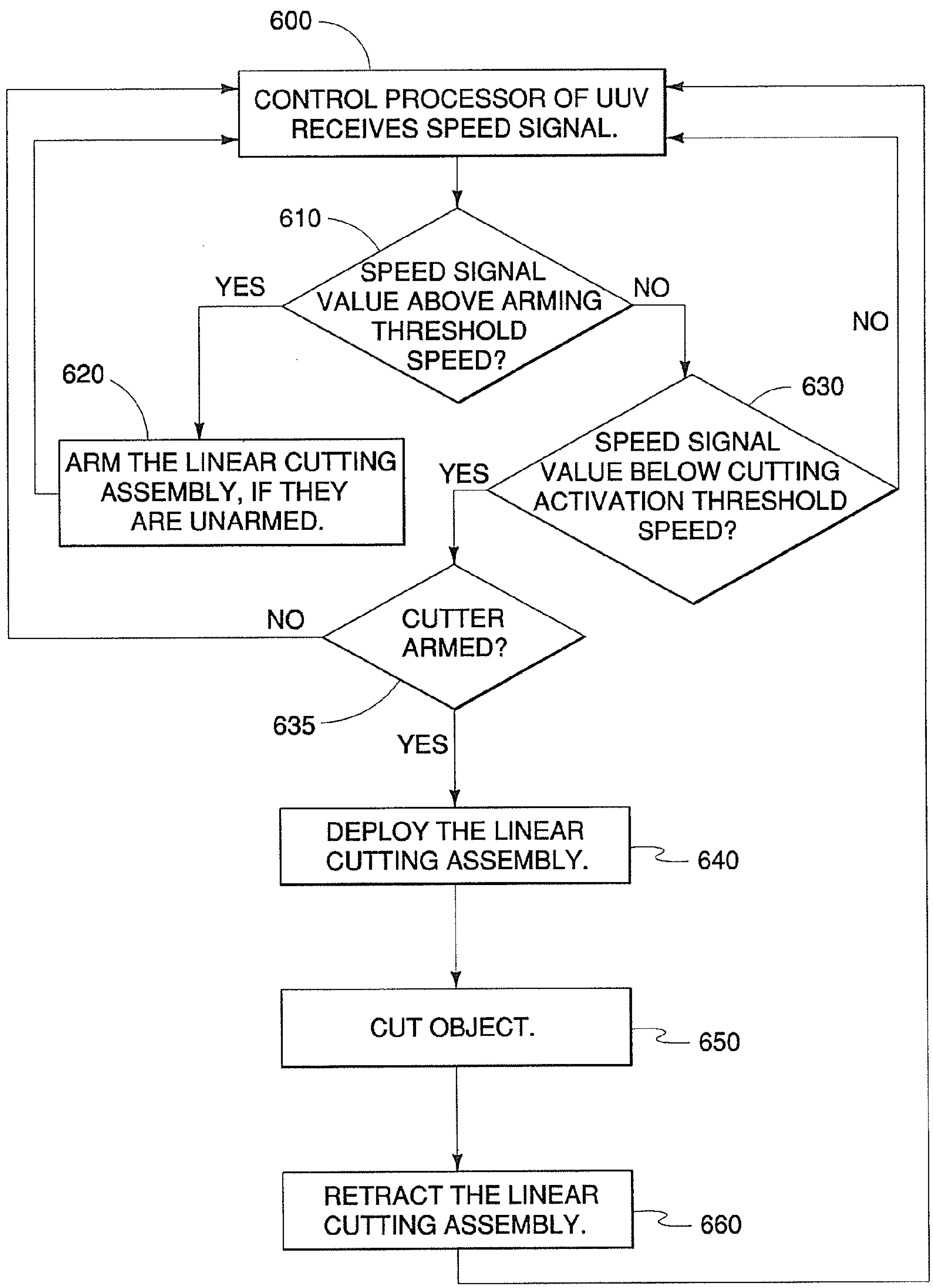


FIG. 5B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CONTROL PROCESSOR OF UUV RECEIVES SPEED SIGNAL.
610
SPEED SIGNAL VALUE ABOVE ARMING THRESHOLD SPEED?
YES
NO
620
ARM THE LINEAR CUTTING ASSEMBLY, IF THEY ARE UNARMED.
630
SPEED SIGNAL VALUE BELOW CUTTING ACTIVATION THRESHOLD SPEED?
YES
NO
CUTTER ARMED?
NO
635
YES
DEPLOY THE LINEAR CUTTING ASSEMBLY.
640
CUT OBJECT.
650
RETRACT THE LINEAR CUTTING ASSEMBLY.
660

FIG. 6

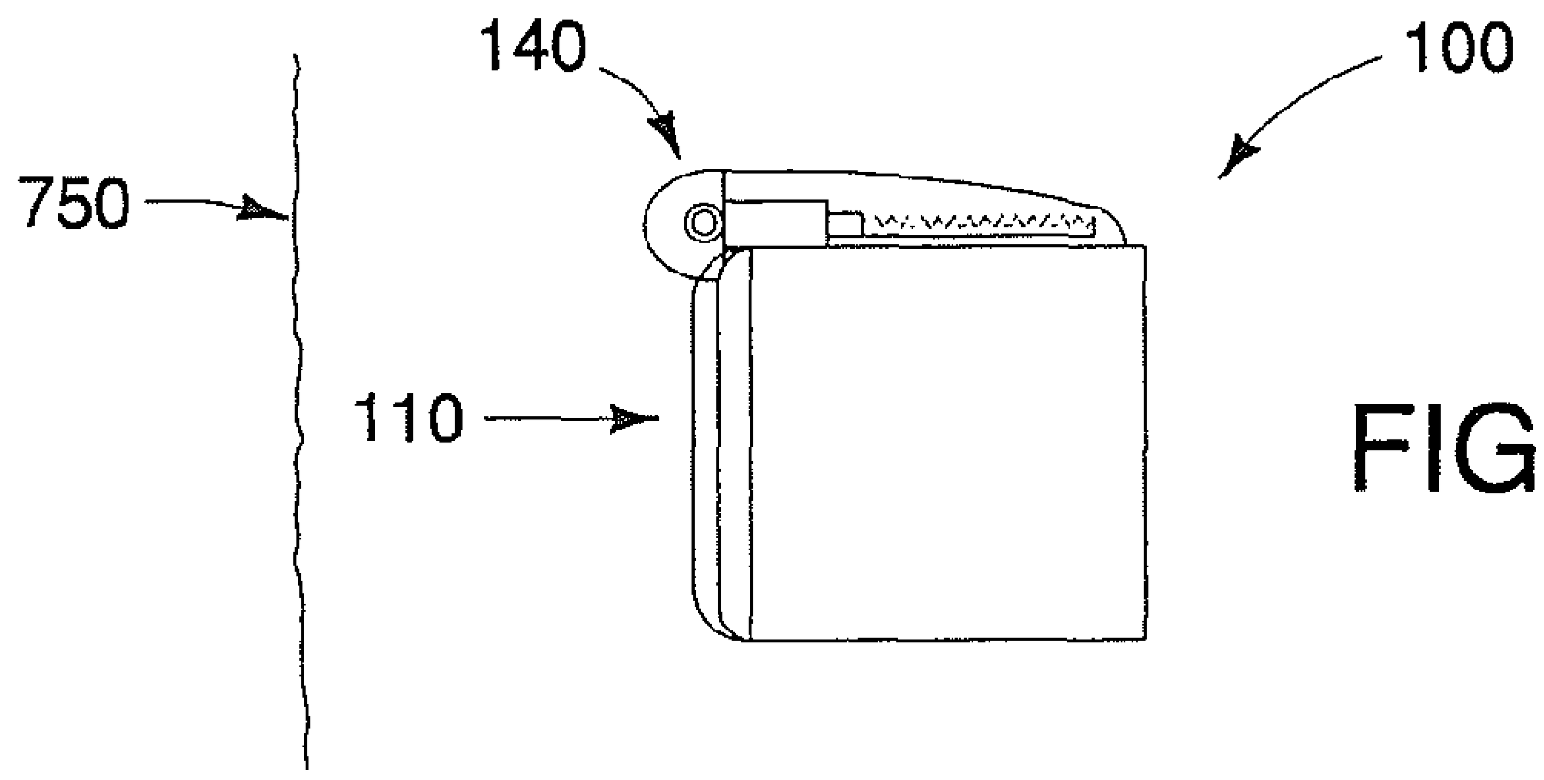

FIG. 7A

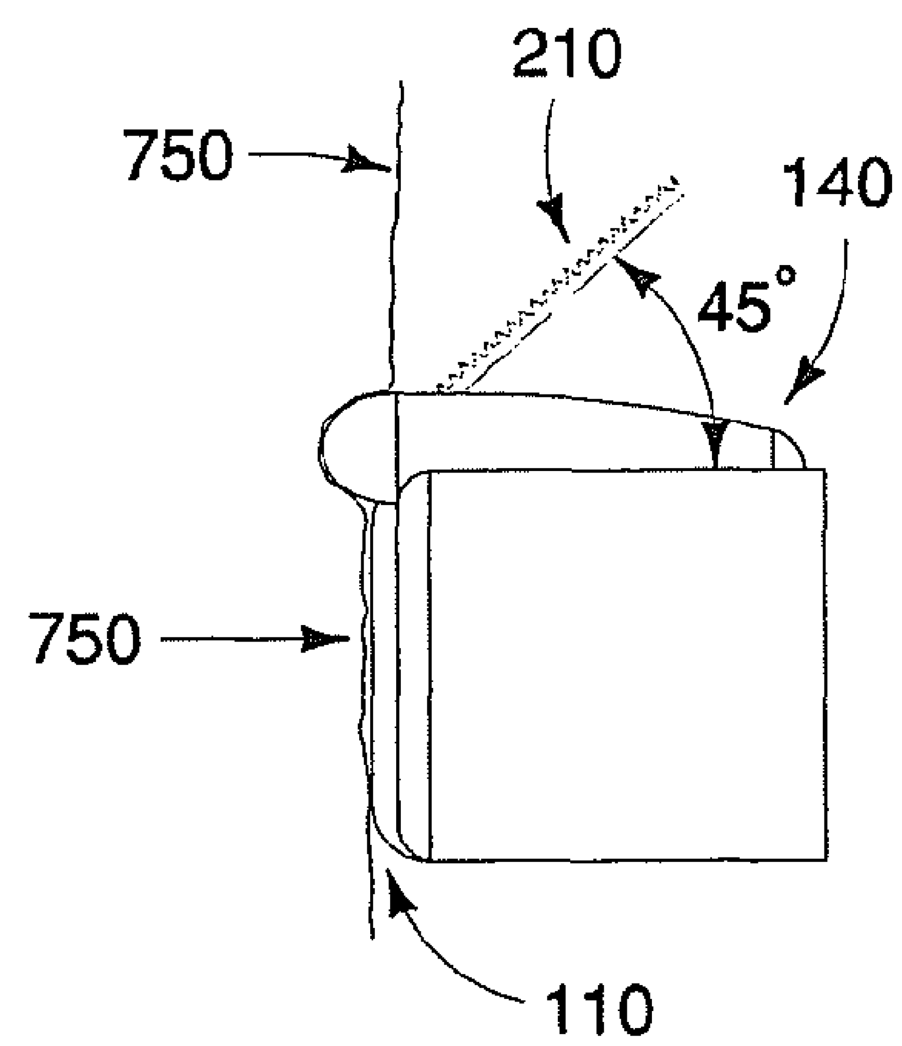

FIG. 7B

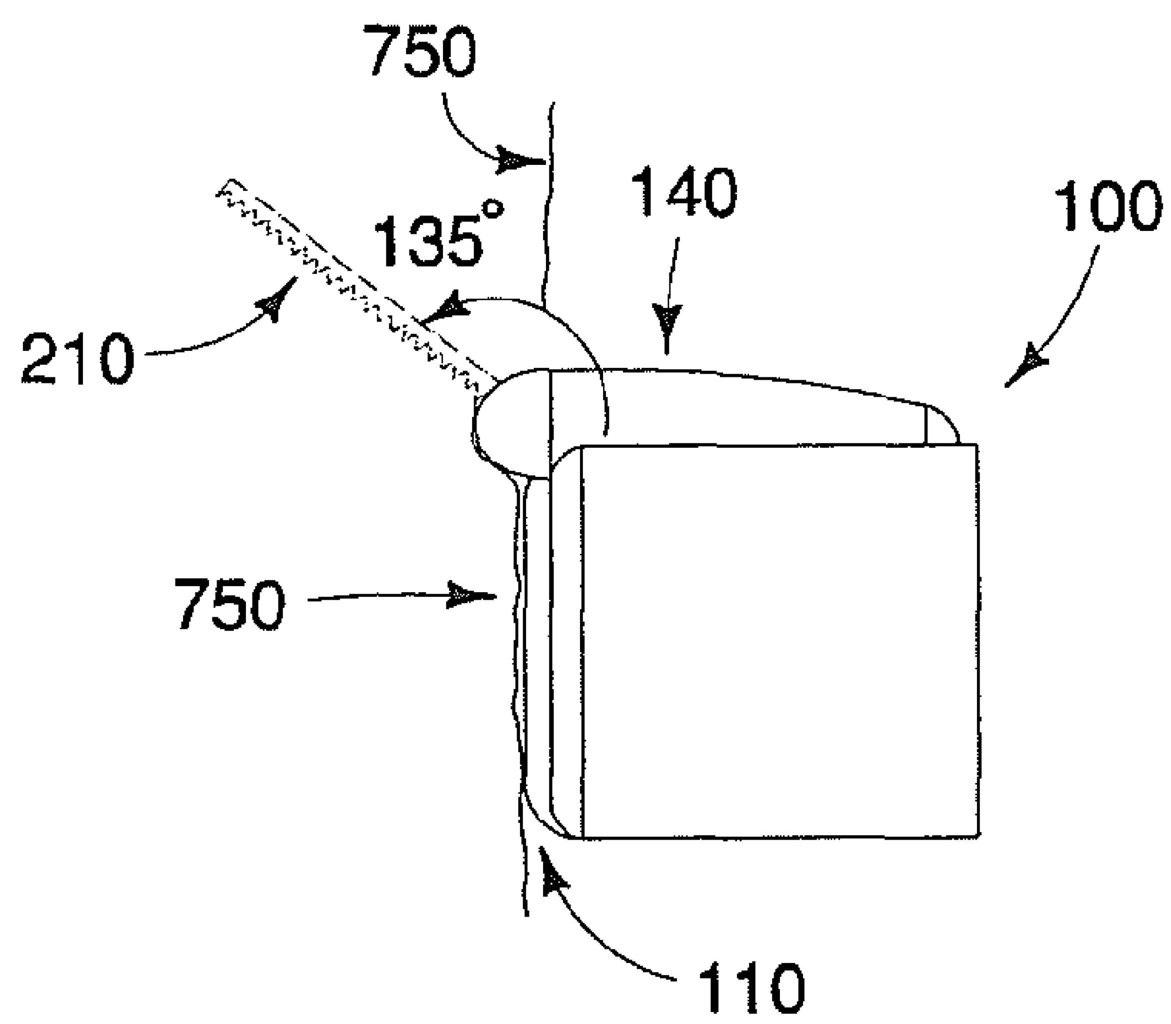

FIG. 7C

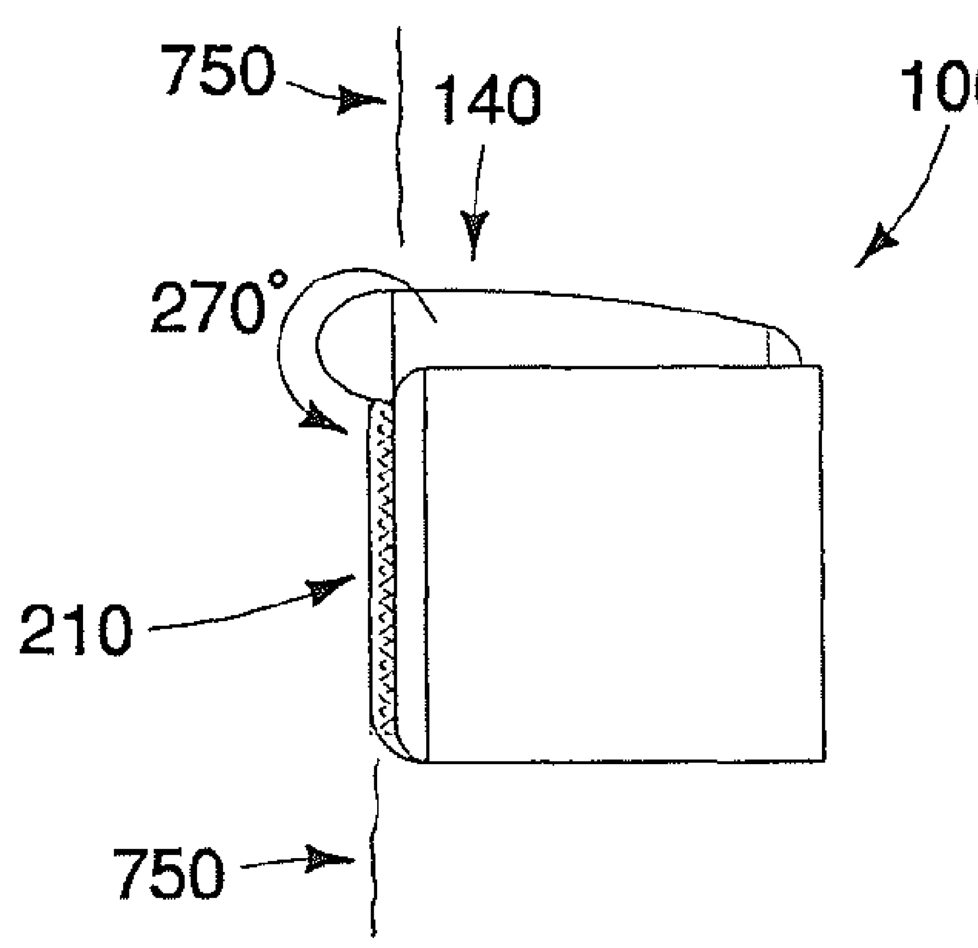

FIG. 7D

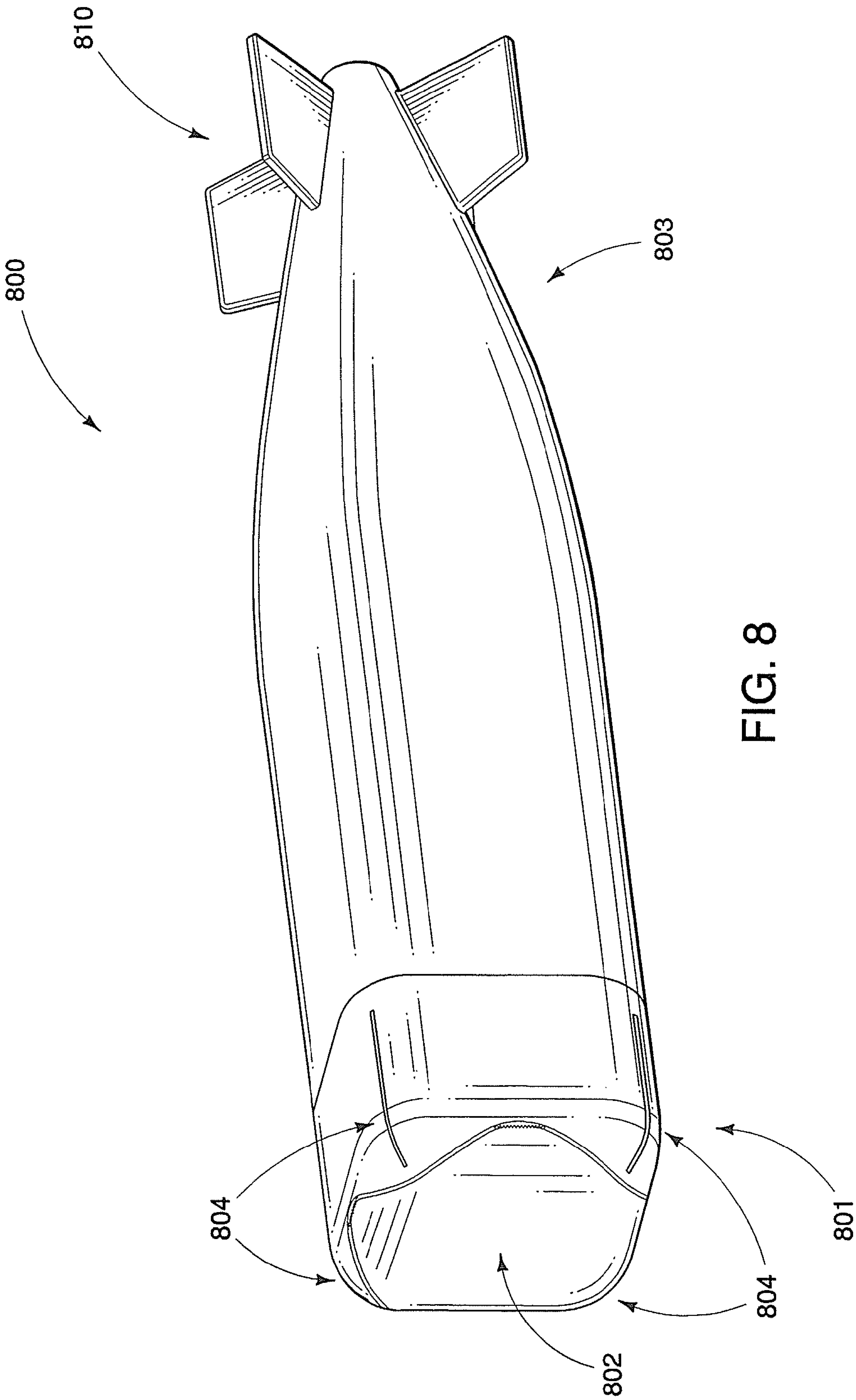

FIG. 8

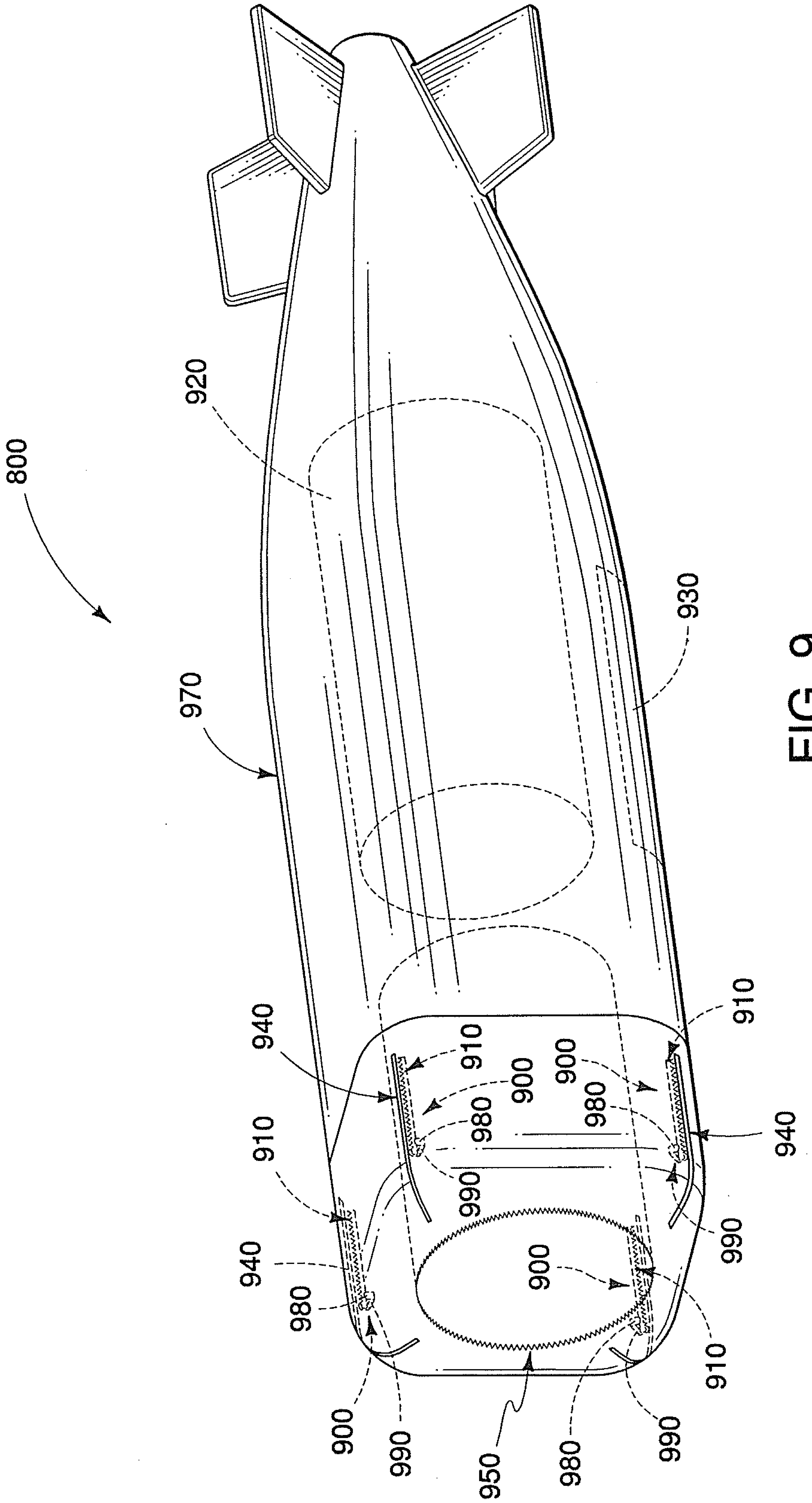

FIG. 9

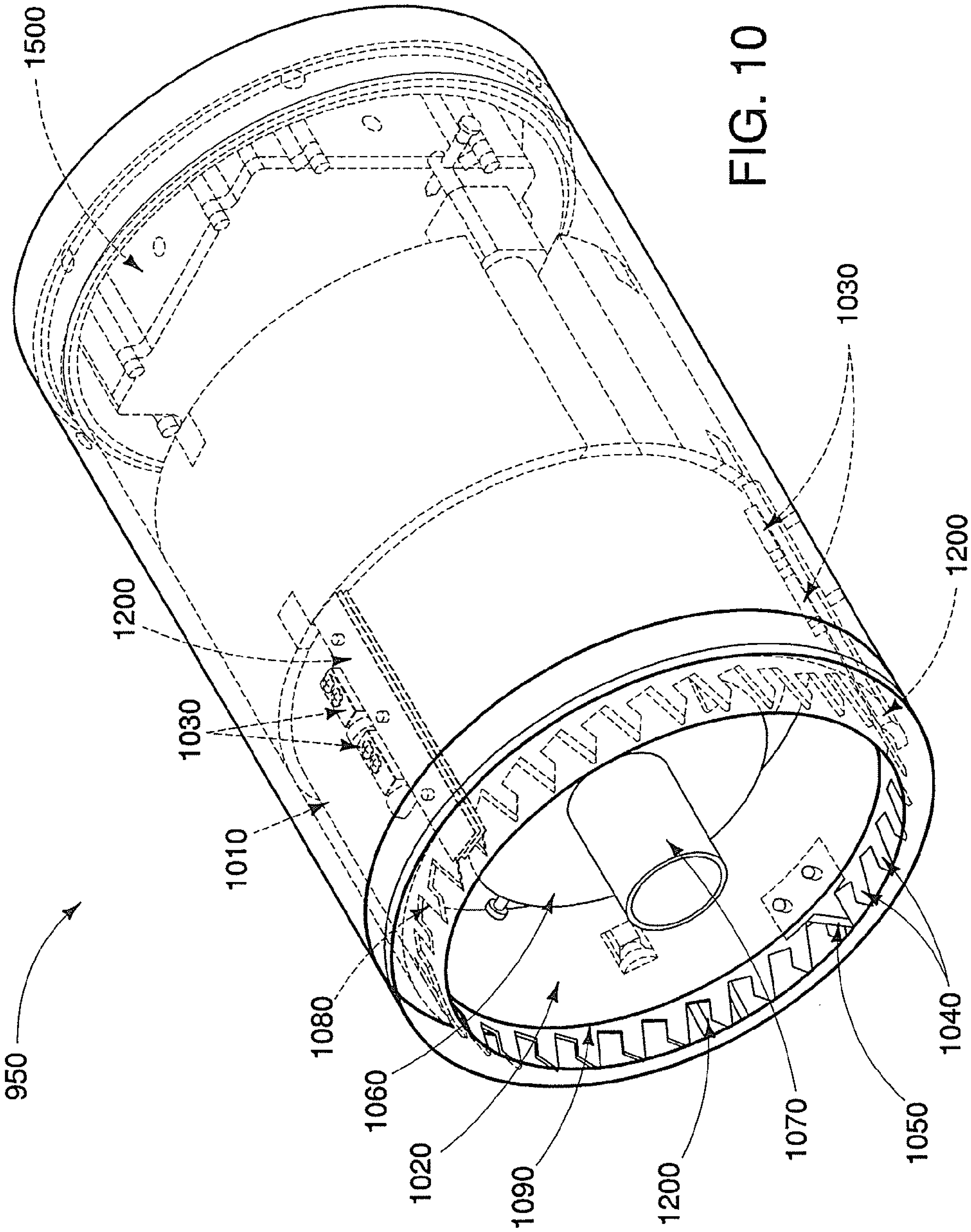
950
1500
1030
1200
1030
1010
1080
1060
1020
1090
1200
1070
1050
1040
1200

FIG. 10

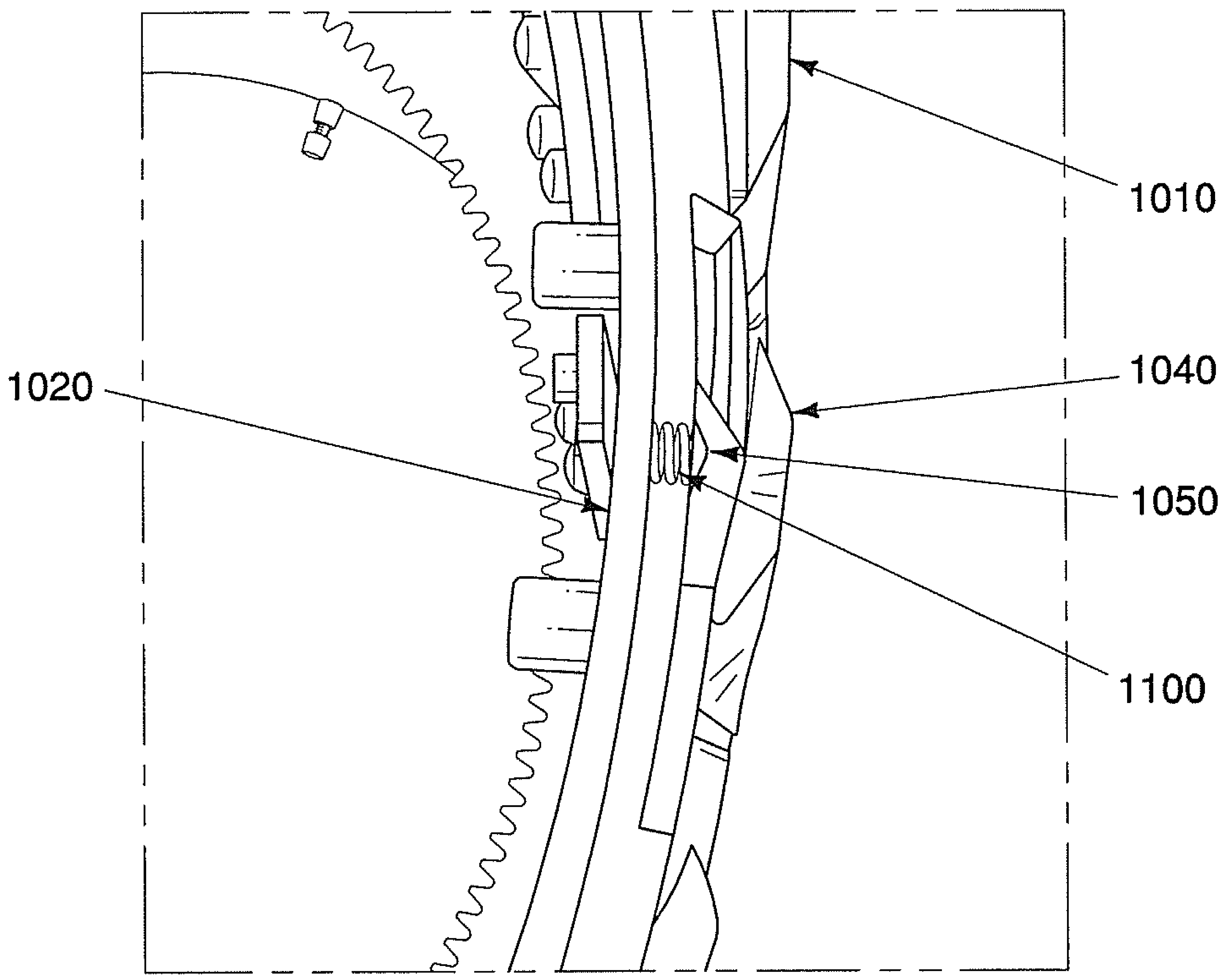

FIG. 11

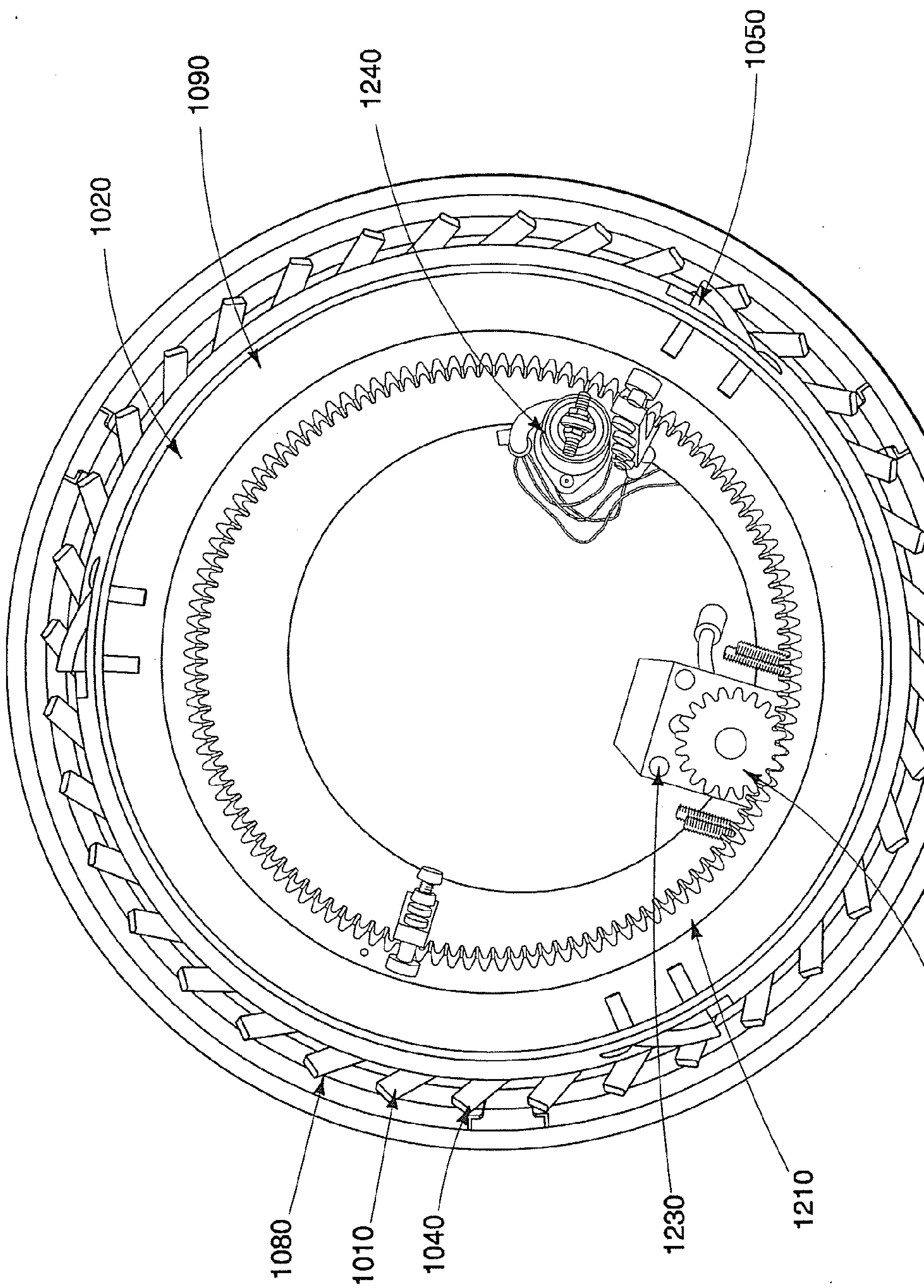

FIG. 12

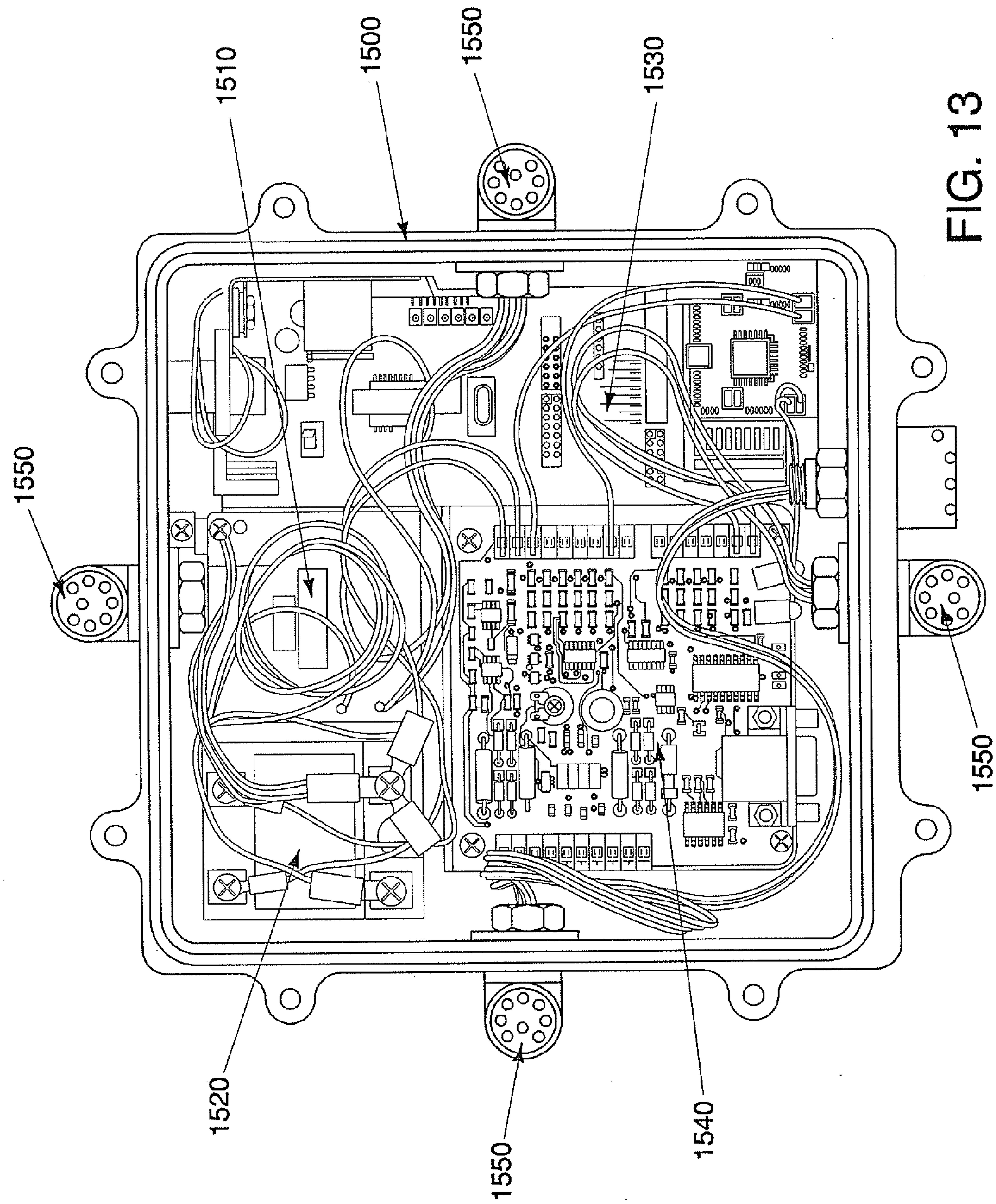

FIG. 13

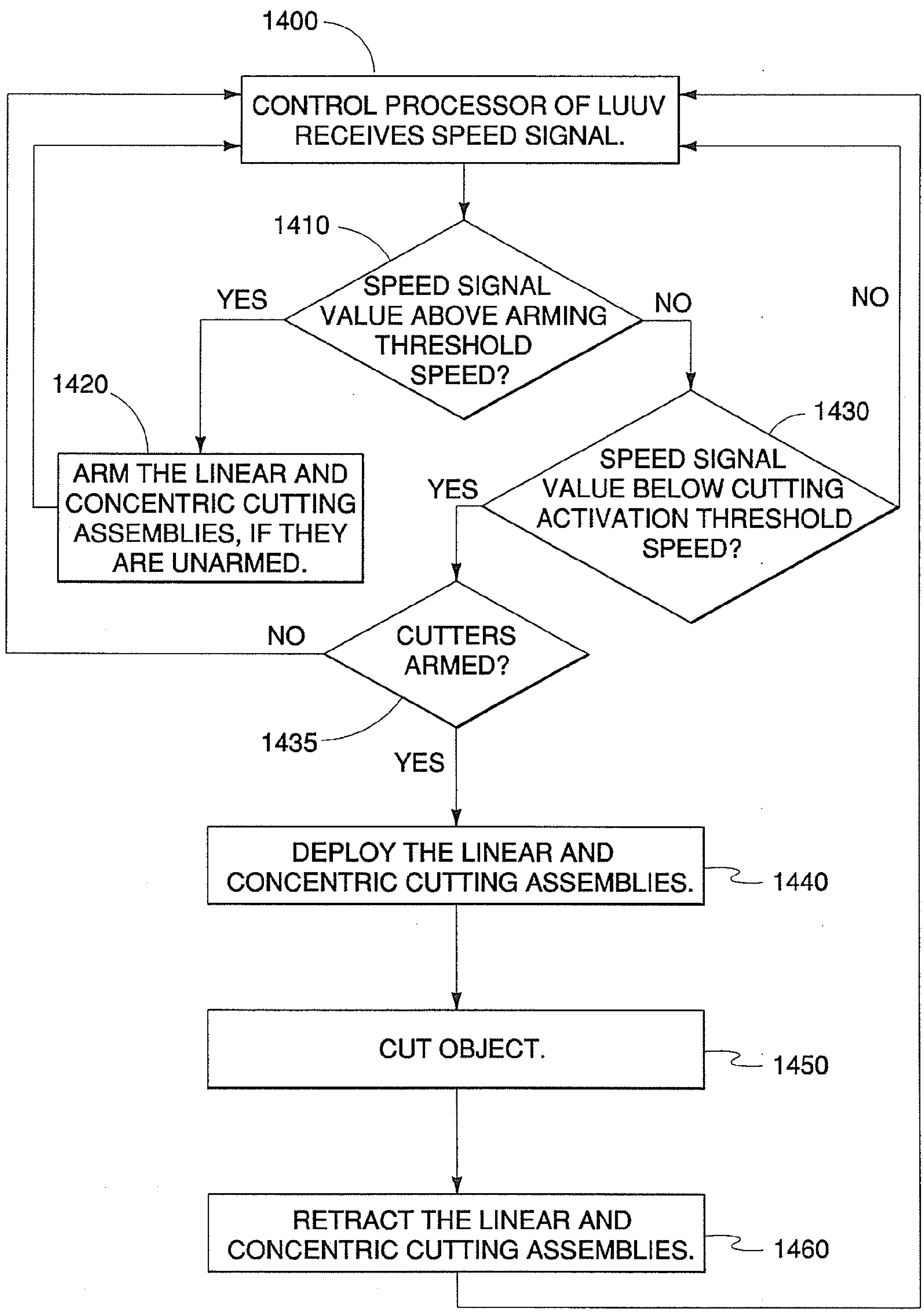
1400
CONTROL PROCESSOR OF LUUV RECEIVES SPEED SIGNAL.
1410
SPEED SIGNAL VALUE ABOVE ARMING THRESHOLD SPEED?
YES
NO
NO
1420
ARM THE LINEAR AND CONCENTRIC CUTTING ASSEMBLIES, IF THEY ARE UNARMED.
1430
SPEED SIGNAL VALUE BELOW CUTTING ACTIVATION THRESHOLD SPEED?
YES
NO
CUTTERS ARMED?
1435
YES
DEPLOY THE LINEAR AND CONCENTRIC CUTTING ASSEMBLIES.
1440
CUT OBJECT.
1450
RETRACT THE LINEAR AND CONCENTRIC CUTTING ASSEMBLIES.
1460

FIG. 14

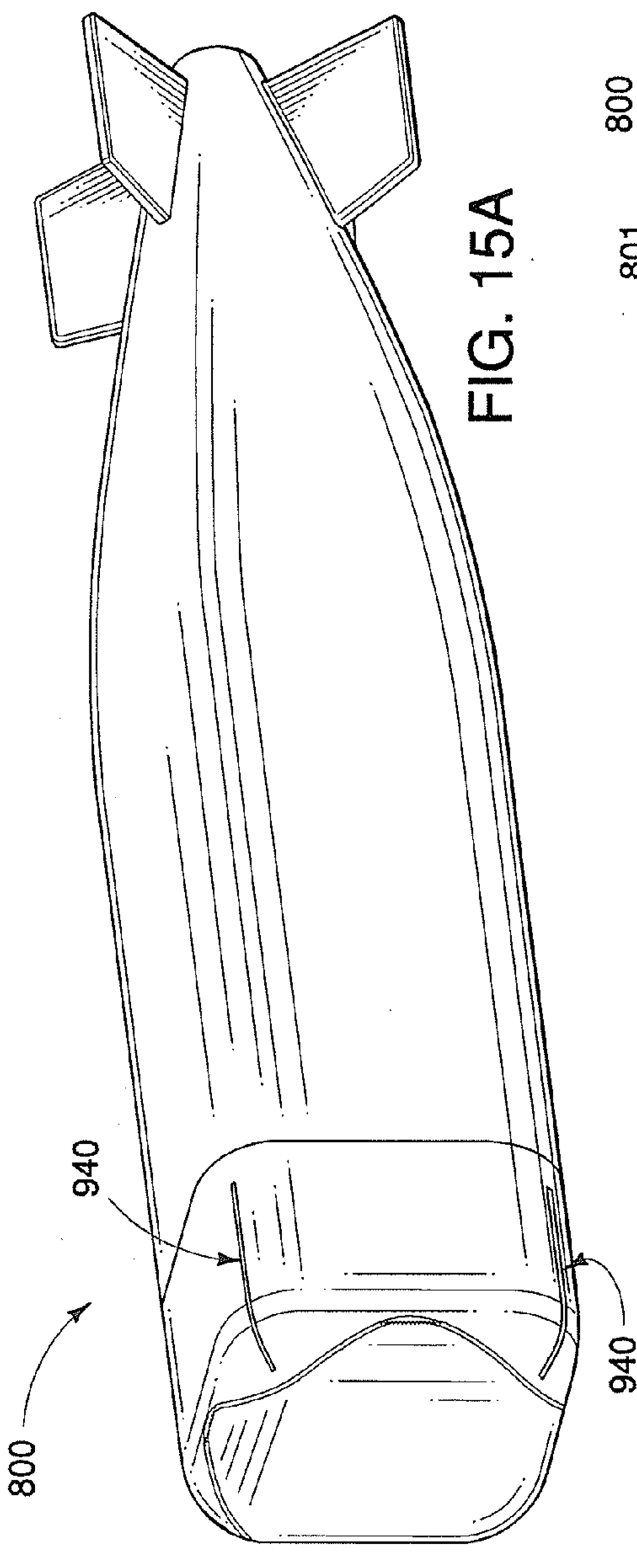

FIG. 15A

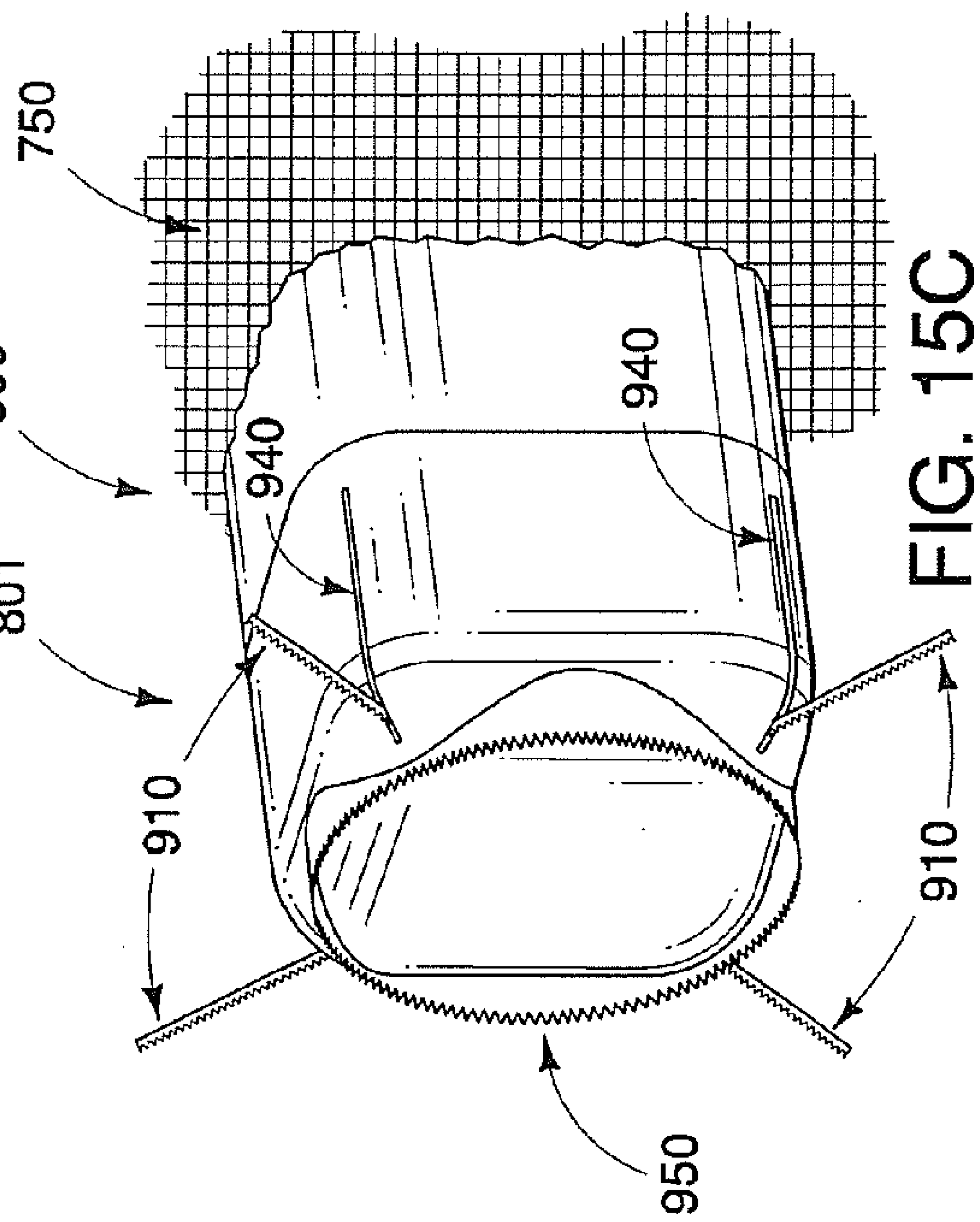

FIG. 15C

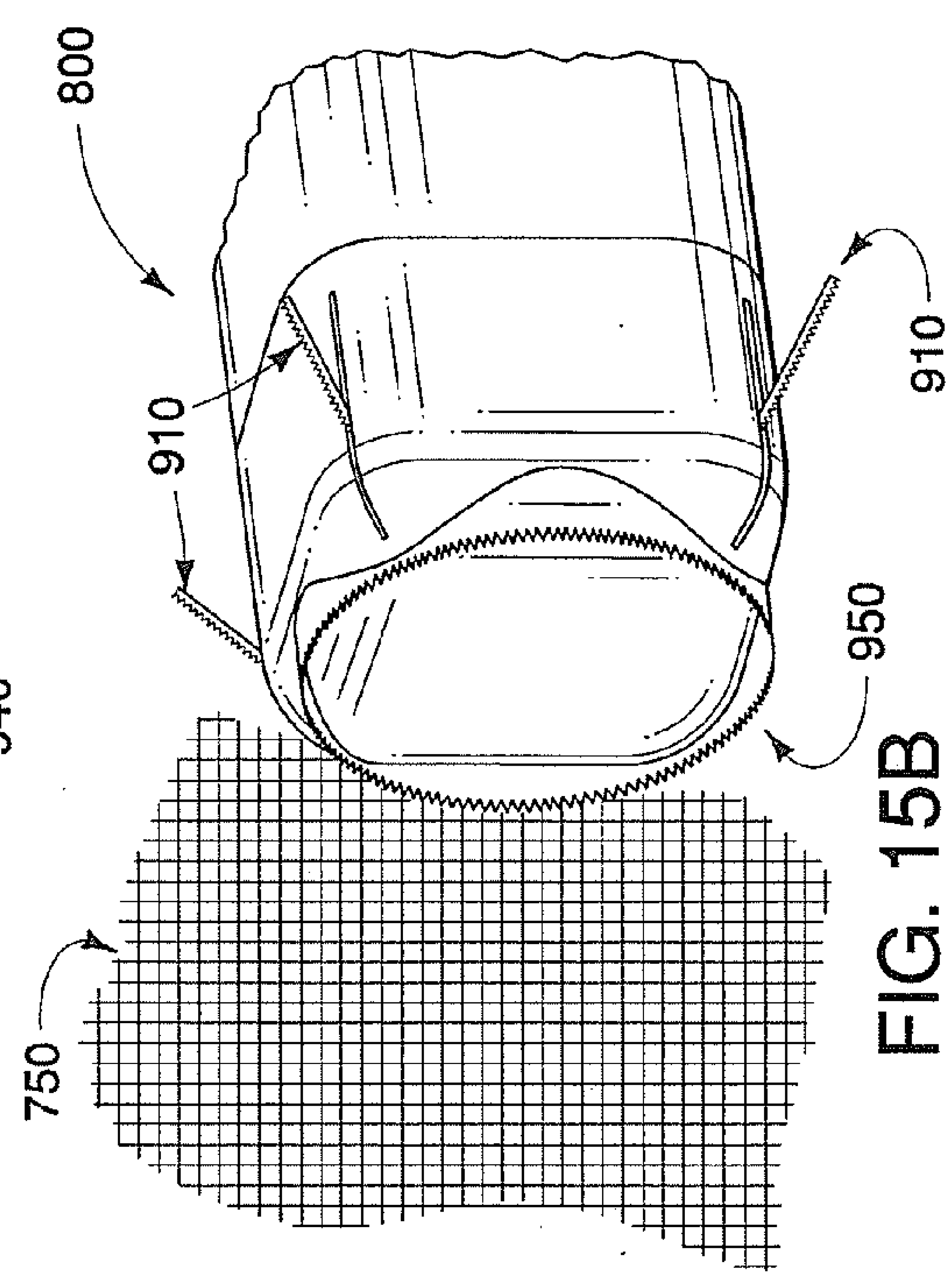

FIG. 15B

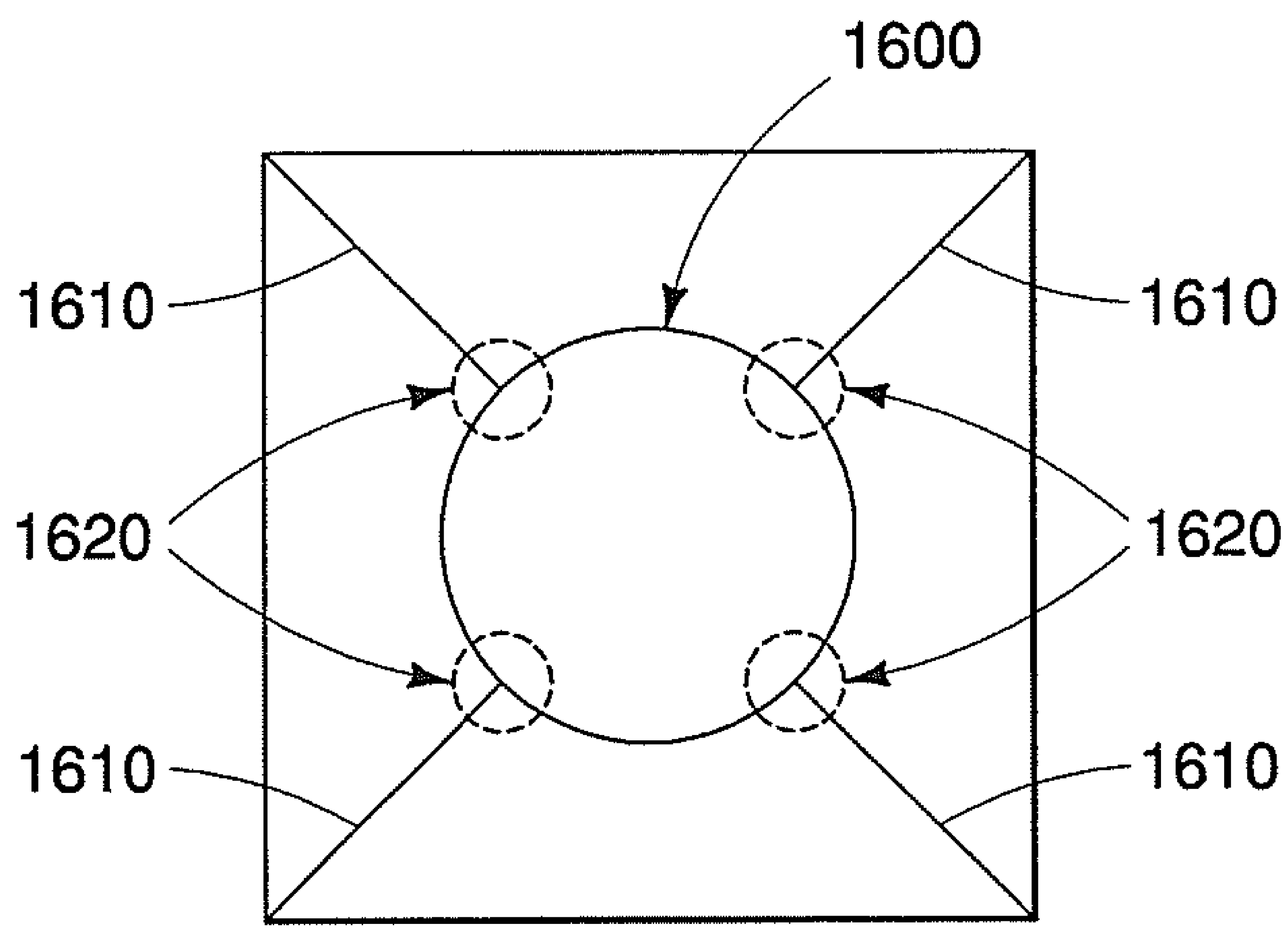

FIG. 16

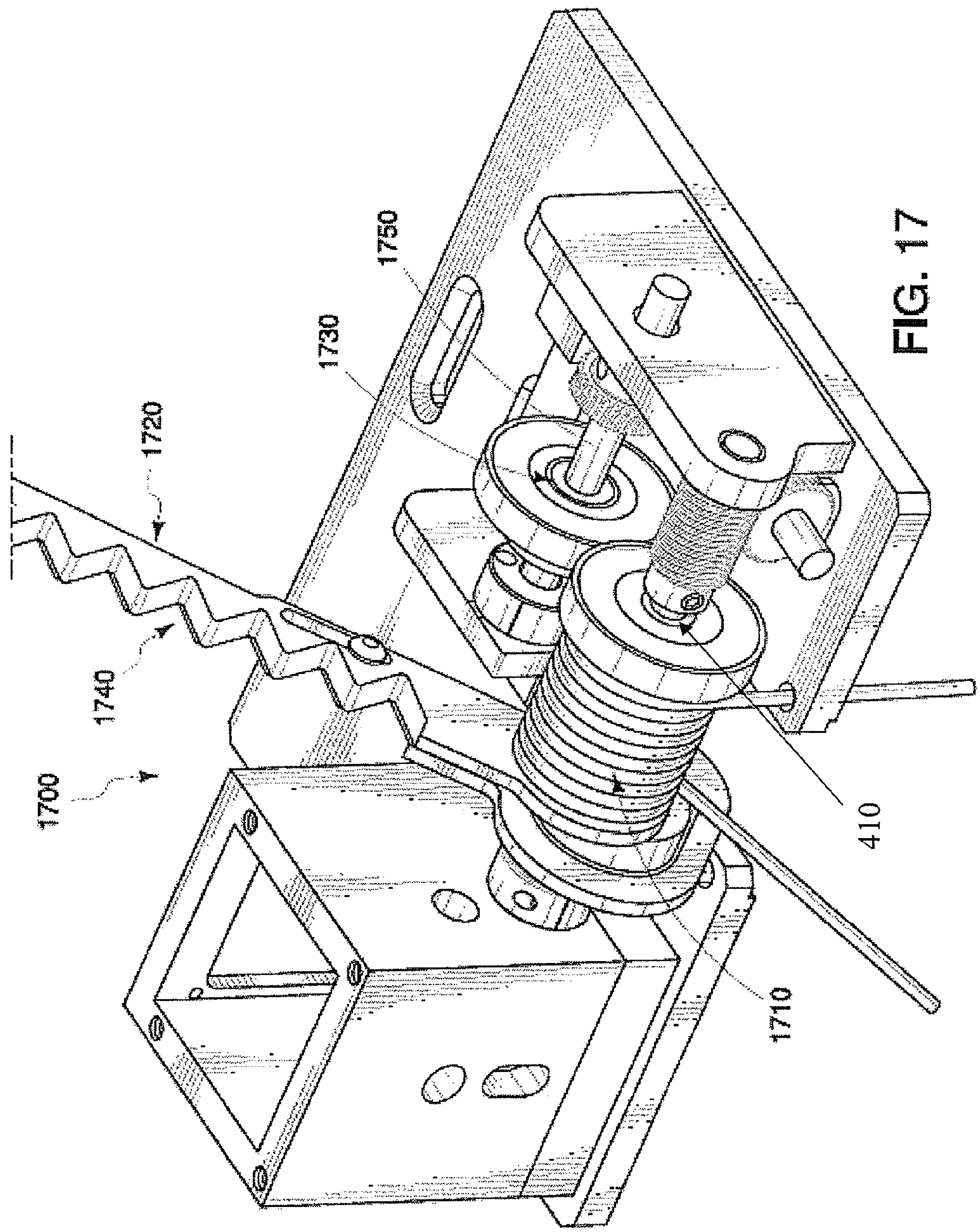

FIG. 17

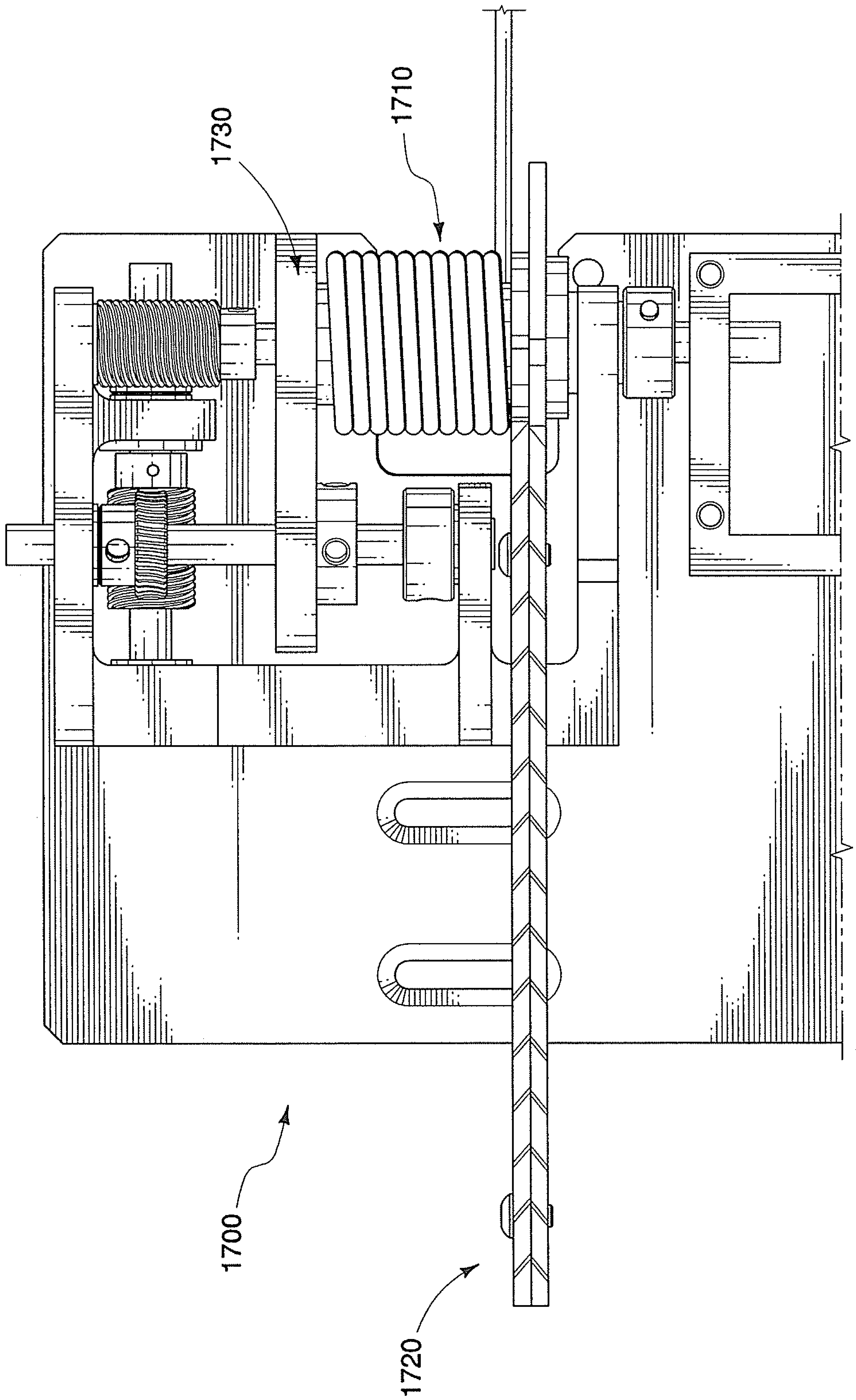

FIG. 18

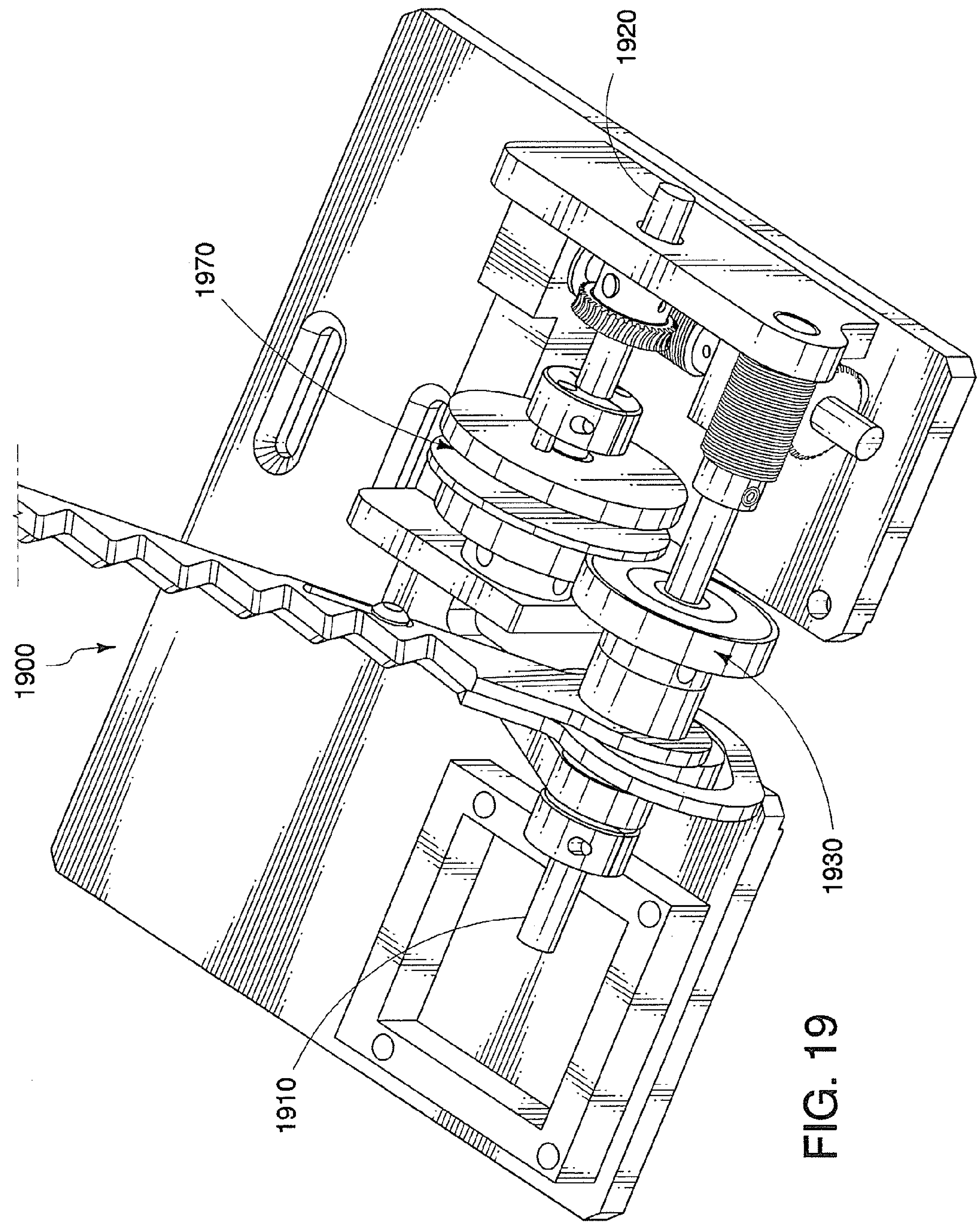

FIG. 19

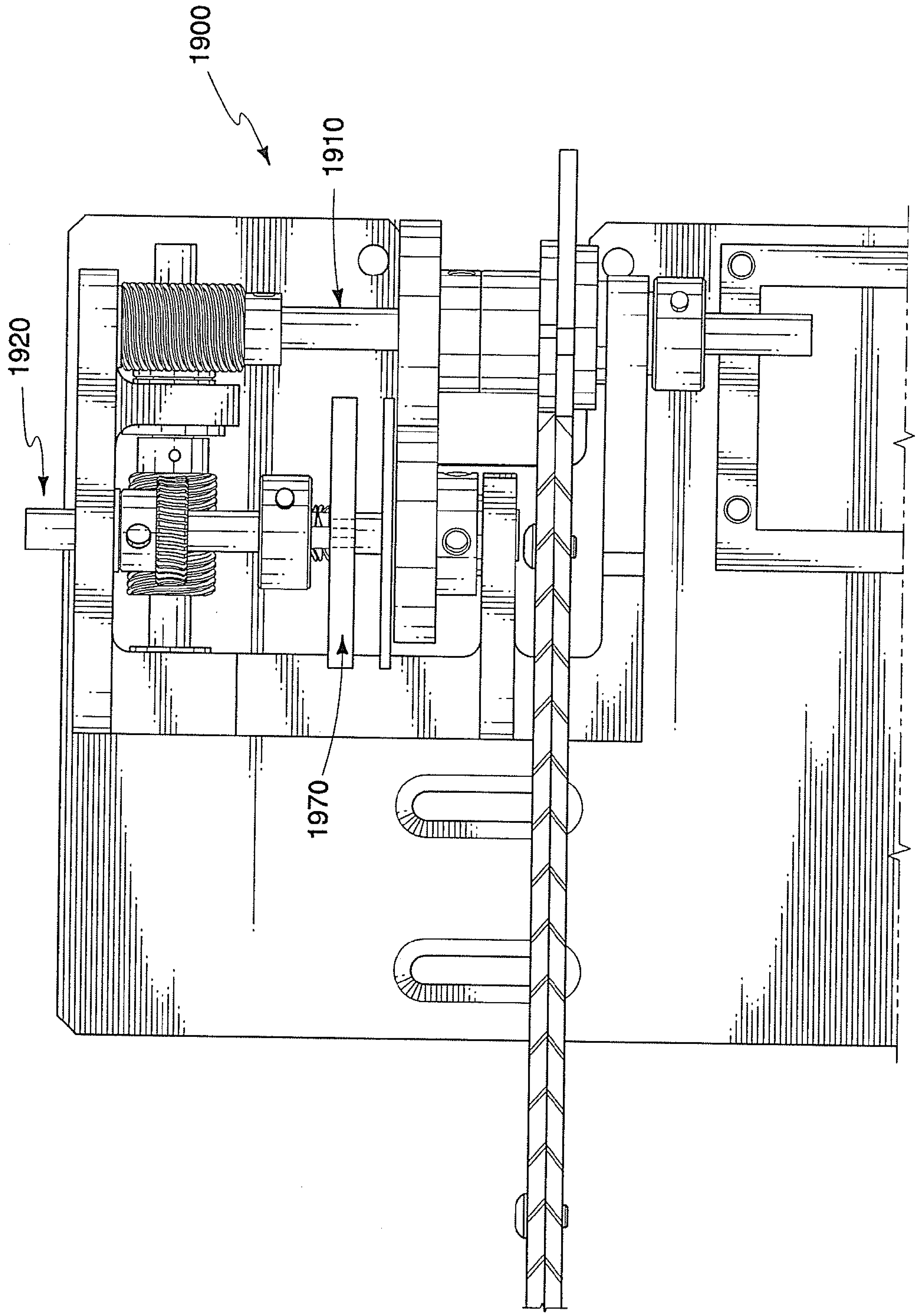

FIG. 20

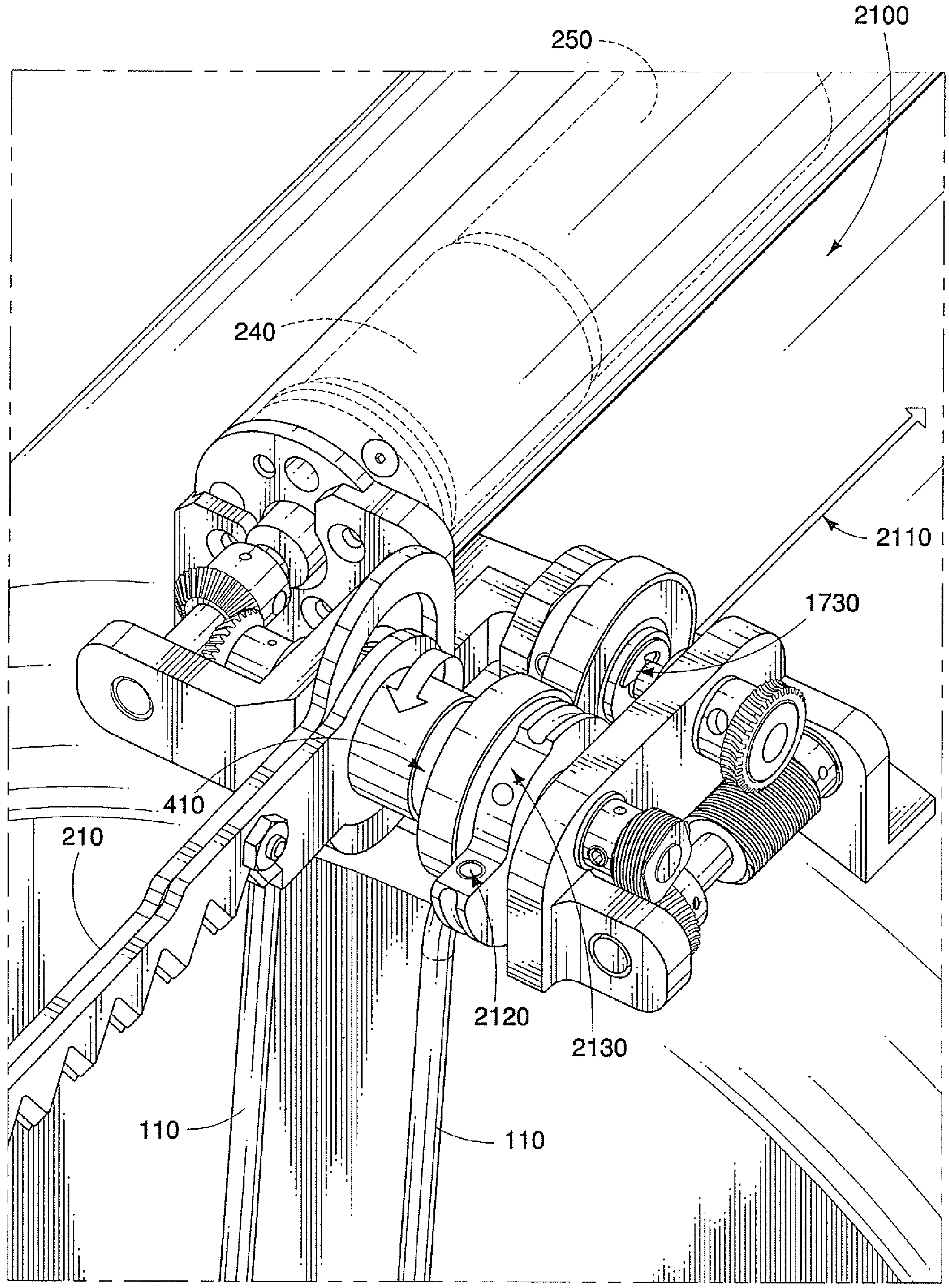

FIG. 21

UNDERWATER VEHICLE CUTTING APPARATUS

This application is a continuation of U.S. application Ser. No. 13/403,491, filed on Feb. 23, 2012, which claims priority under 35 U.S.C. §119(e) to Provisional Application No. 61/445,847 filed on Feb. 23, 2011, which is incorporated herein by reference.

FIELD OF THE INVENTION

The invention relates generally to a cutting assembly, and in particular to a system, method, and apparatus for cutting nets and other objects.

BACKGROUND

Nets of various types, materials, sizes and shapes such as, gill nets, purse nets, trawl nets, lift nets, drift nets and aquaculture nets, among others, may cover large areas of the ocean and create physical barriers to moving marine vessels and underwater vehicles. Marine vessels and underwater vehicles can encounter these nets and others in a variety of orientations and tensions. Nets can be anchored and tightly strung, be loose and compliant, or float with weights distributed on the bottom. The use of fishing nets and other objects in water bodies present a significant obstacle to marine vessels and underwater vehicles, especially in littoral zones where fishing activity is concentrated.

Unmanned underwater vehicles (UUVs) have contributed greatly to the gathering of information in harbors and littoral waters where other underwater vehicles such as submarines cannot travel or may be easily detected. For example, UUVs can carry out critical missions in the areas of intelligence, surveillance, reconnaissance, mine countermeasures, tactical oceanography, navigation and anti-submarine warfare. Mission performances, however, have been hindered by a UUV's inability to penetrate through fishing nets and other objects while traveling underwater.

Presently, UUV mission areas are scanned for fishing nets and other objects. Mission routes are selected so as to minimize the probability of encountering objects even though the selected route may not be the shortest or the most desired route. Yet, UUVs may be called upon during mission critical situations to penetrate waters in which there is a high probability of encountering fishing nets and other objects. In these situations, a UUV may be forced to stop and maneuver around obstacles encountered during its mission. Even the smallest hull protrusions, such as the control fins, sonar pods and antenna masts of a UUV, may get entangled in a fishing net. Once entangled, divers may be required to retrieve the UUV and cause significant operation delay. Operation failure may result if the UUV is not retrievable or lost altogether.

Accordingly, there is a need and desire for an apparatus, system and method for easily and quickly penetrating through nets and other objects.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. **1** is a diagram of a UUV system in accordance with an embodiment described herein.

FIG. **2** is a profile view of a linear cutting assembly in accordance with an embodiment described herein.

FIG. **3** is a side view of a stationary blade and a moveable blade of a linear cutter arm in accordance with an embodiment described herein.

FIG. **4**A is a profile view of a cam assembly of a linear cutting assembly in accordance with an embodiment described herein.

FIG. **4**B is a profile view of a clutch assembly of a linear cutting assembly in accordance with an embodiment described herein.

FIG. **4**C is a front view of a portion of the linear cutting assembly in accordance with an embodiment described herein.

FIG. **5**A is a front view of the UUV system of FIG. **1**.

FIG. **5**B is a side view of a portion of the UUV system of FIG. **1**.

FIG. **6** is a flow chart of a method for penetrating through a net using a linear cutting assembly in accordance with an embodiment described herein.

FIGS. **7**A-**7**D respectively illustrate a linear cutting assembly in a 0 degree, a 45 degree, a 135 degree and a 270 degree rotating motion in accordance with an embodiment described herein.

FIG. **8** is a diagram of a LUUV system in accordance with an embodiment described herein.

FIG. **9** illustrates the LUUV system of FIG. **8** having a concentric cutting assembly and linear cutting assemblies.

FIG. **10** is an internal view showing the components of a concentric cutting assembly in accordance with an embodiment described herein.

FIG. **11** is a profile view of a concentric cutting assembly in accordance with an embodiment described herein.

FIG. **12** shows an inside view of a concentric cutting assembly in accordance with an embodiment described herein.

FIG. **13** is a schematic diagram of an electronic assembly of a concentric cutting assembly in accordance with an embodiment described herein.

FIG. **14** is a flow chart of a method for penetrating through a net using a combination cutting module in accordance with an embodiment described herein.

FIG. **15**A illustrates cutting assemblies of a LUUV system in an armed state in accordance with an embodiment described herein.

FIG. **15**B illustrates cutting assemblies of a LUUV system in a deployed state in accordance with an embodiment described herein.

FIG. **15**C illustrates cutting assemblies of a LUUV system cutting a fishing net or object in accordance with an embodiment described herein.

FIG. **16** illustrates cuts made by the cutting assemblies of a LUUV system in accordance with an embodiment described herein.

FIGS. **17** and **18** illustrate a profile view and a top-down view respectively of a linear cutting assembly in accordance with another embodiment described herein.

FIGS. **19** and **20** illustrate a profile view and a top-down view respectively of a linear cutting assembly in accordance with another embodiment described herein.

FIG. **21** is a simplified diagram of a linear cutting assembly in accordance with an alternate embodiment described herein.

DETAILED DESCRIPTION OF THE INVENTION

In the following detailed description, reference is made to the accompanying drawings, which form a part hereof and illustrate specific embodiments that may be practiced. In the drawings, like reference numerals describe substantially similar components throughout the several views. These embodiments are described in sufficient detail to enable those skilled in the art to practice them, and it is to be understood that structural and logical changes may be made. Sequences of steps are not limited to those set forth herein and may be changed or reordered, with the exception of steps necessarily occurring in a certain order.

The problem of penetrating through nets and other objects is solved by cutting the object using a linear cutting assembly having a linear cutter arm that moves in an arc and pivots about an attachment point. The net is cut by a severing action caused by a moveable blade of the linear cutting arm moving back and forth across a stationary blade of the linear cutter arm. A linear cutting assembly that is attached to an underwater vehicle will cut a sufficiently large opening in the net to allow the vehicle to pass through.

Disclosed embodiments include a system and method for penetrating through fishing nets and other objects, as well as various apparatuses, including a linear cutting assembly, for use in this system. Embodiments of the linear cutting assembly include a linear cutter arm with a moveable blade having teeth that slide back and forth against the teeth of a stationary blade.

The invention may be used to particular advantage in the context of underwater vehicles traveling in areas with high fishing activity. Therefore, the following example embodiments are disclosed in the context of UUV systems. However, it will be appreciated that those skilled in the art will be able to incorporate the invention into numerous other alternative systems that, while not shown or described herein, embody the principles of the invention.

FIG. **1** shows a UUV system **100** in accordance with an embodiment described herein. UUV **100** has two parallel spaced cutter guides **110** at the forward end **101** for keeping a net or object away from the front face **102** of the UUV **100**. At the aft end **103**, UUV **100** has a propulsor **130** and hull protrusion **120**. Attached on the outside of the forward end **101** of UUV **100** is a pod **140** containing a linear cutting assembly **200** (FIG. **2**). A control container **150** containing a control processor for controlling the UUV **100** and the linear cutting assembly **200** functions, a memory for storing control software and an I/O processor is located in the rear bottom of UUV **100**, although it shall be appreciated that the control container **150** can be located anywhere in UUV **100**. The control processor is the main processor for UUV **100** and will run the control software for the linear cutting assembly **200**. Because the linear cutting assembly **200** is contained in the pod **140** and the pod **140** is attached externally to the UUV **100**, the linear cutting assembly **200** can be easily installed, removed, and repaired at sea. The pod **140** is lightweight and has minimal effect on the static and dynamic balance of the UUV **100**.

FIG. **2** is a profile view of an exemplary linear cutting assembly **200** that can be housed in the pod **140** of UUV **100**. Linear cutting assembly **200** includes a linear cutter arm **210**, a gear housing **220** containing bevel gears **230**, a gear box **240** integrated with a DC motor **250**, a cam assembly **260**, a clutch assembly **270** and a frame structure **280** attached to a base plate **290**. The base plate **290** is attached to the inside bottom surface of the pod **140** using fasteners **295** or other suitable means. The DC motor **250** is mated with a gearhead. The integrated DC motor **250** produces a predetermined amount of power such as, for example about 120 watts of motor power, based on the expected UUV power source. Alternatively, it will be appreciated that other suitable gearing concepts, such as, a worm gear system, a planetary gear set, among others, can be incorporated to drive the cutting assembly **200**.

FIG. **3** shows a side profile of the linear cutter arm's **210** stationary blade **300** separated from its moveable blade **310**. The stationary blade **300** is located parallel to, and preferably in contact with, the moveable blade **310** when the cutter arm **210** is assembled as shown in FIG. **2**. A peg **320** and slot **330** can be used to ensure that the blades **300** and **310** remain in contact and in alignment over the entire cutting length and allow the blades **300** and **310** to slide linearly between them. The moveable blade **310** will slice through the net or object as it moves back and forth across the stationary blade **300**. A UUV **100** such as, for example, a vehicle having a 12.75 inch diameter, preferably has stationary **300** and moveable **310** blades that are approximately 14 inches long.

The reciprocating teeth **340** and **350** of the stationary **300** and moveable **310** blades, respectively, are effective at cutting in both directions. FIG. **3** shows the teeth **340** and **350** are triangular shaped and each tooth is located equidistant from each other. The teeth must be sized correctly to effectively engage the net. If the teeth are too wide, they will not fit into the holes of smaller-meshed nets. If the teeth are too short, they will not provide an adequately long cutting surface for the floating teeth to move against. As tooth length increases, however, it becomes more susceptible to damage. Preferably, the teeth **340** and **350** have peak-to-peak spacing of approximately 0.5 inch apart and have angles of approximately 50 degrees on both sides. It will be appreciated that the tooth angle, length, tip and base radii, and arm thickness can vary based on the size of the opening to be cut and performance parameters, such as the length of cutting time.

The blades **300** and **310** and teeth **340** and **350** may be manufactured from stainless steel or any other anti-corrosive material, such as, but not limited to plastic, titanium, carbon fiber and coated steel. A hardened surface coating, such as, titanium-nitride, or a low-friction material may be applied to the teeth to increase wear resistance and reduce power usage.

FIG. **4**A is a profile view of the cam assembly **260** of the linear cutting assembly **200**. The cam assembly **260** transforms the rotating motion of the offset cam **400** into linear motion of the moveable blade **310** to allow the moveable blade **310** to move linearly back and forth along the longitude of the stationary blade **300**. The offset cam **400** and shaft collar **440** are fixed to the drive shaft **410** and rotated by the gears **230** and motor **250** (FIG. **2**). One advantage of the disclosed embodiment is the design of the mechanical clutch assembly **270**, as shown in FIG. **4**B, and the use of the single motor **250** to control the deployment and retrieval motions of the linear cutter arm **210** and the linear motion of the moveable blade **310**. As illustrated in FIG. **4**C, the springs **430** push the clutch plate **420** axially across the rotating shaft **410** to provide the necessary force to drive the linear cutter arm **210** through the net. When the arm **210** meets sufficient resistance, its forward motion will slow and the clutch **270** will slip, providing more time to cut through the net. It will be appreciated by those skilled in the art that the clutch assembly **270** may need to be geared to allow better net engagement.

FIGS. **17** and **18** illustrate a profile view and a top-down view respectively of another exemplary linear cutting assembly embodiment **1700**. The differences between linear cutting assemblies **200** and **1700** are explained below. Linear cutting assembly **1700** includes a torsion spring **1710** to drive the linear cutter arm **1720** forward independent of the front shaft **410** and a geared one-way bearing **1730** to retract the linear cutter arm **1720**. The one-way bearing **1730** locks to the rear shaft **1750** when the motor is reversed to retract the linear cutter arm **1720**.

FIG. **21** is a simplified diagram of a linear cutting assembly **2100** incorporating a linear cutter arm **210**, in accordance with an alternate embodiment of the present invention. This embodiment is similar to that shown in FIGS. **17-18**, however instead of relying on a torsion spring, the linear cutting assembly **2100** utilizes a linear spring **2110** to rotate the linear cutter arm **210** forward. The one-way bearing **1730** allows the motor **250** to retract the linear cutter arm **210** and stores energy in the linear spring **2110**. The linear spring **2110** is mounted to the front shaft **410** at the spring mounting point **2120** on the cam assembly **2130**. This embodiment has the advantage of allowing all motor power to be used to oscillate the blades **300** and **310** of the linear cutter arm **210** back and forth to cut through the object.

Another exemplary linear cutting assembly embodiment **1900** that can be housed in the pod **140** of UUV **100** has a reduced RPM clutch assembly **1970** as illustrated in FIGS. **19** and **20**. The differences between linear cutting assembly embodiments **200**, **1700** and **1900** are explained below. Linear cutting assembly **1900** has a front shaft **1910** and a rear shaft **1920**. The offset cam **1930** is fixed to the front shaft **1910** and rotated by gears and a motor similar to the gears **230** and motor **250** shown in FIG. **2**. In contrast to the clutch assembly **270**, the clutch assembly **1970** is located on the rear shaft **1920** and geared down to minimize slippage, preferably a 100:1 gear reduction. The clutch assembly **1970** operates at $\frac{1}{1000}$th of the motor speed or approximately 8 RPM.

FIG. **5**A is a front view of the UUV system **100** shown in FIG. **1**. The maximum cross section of the pod **140** is an ellipse. As shown in the present embodiment, the pod has a major axis of approximately 4.4 inches and a minor axis of approximately 3.5 inches. However, any sized pod can be used. The pod **140** containing the linear cutting assembly **200** has an hydrodynamic shape as shown in FIGS. **5**A and **5**B to minimize drag as UUV **100** moves underwater and to minimize the power required for the linear cutting assembly **200** to penetrate through the net. A UUV **100** for example has a pod **140** that is approximately 15.5 inches long and that gradually tapers toward the aft end **103** (FIG. **1**) of the vehicle **100**. Again, the size of the pod can vary. A preferred height of the pod **140** above the exterior of the vehicle **100** is approximately 2.5 inches as shown in FIG. **5**B. Minimizing the frontal area and overall surface area of the pod **140** will reduce hydrodynamic drag and help maximize mission duration. Syntactic foam, for example, can be placed inside the pod **140** to balance the linear cutting assembly **200** and add structural support to the pod **140**. The pod **140** can be attached to the UUV **100** through the use of fasteners mounted to hull attachment points **160**. Alternatively, the pod **140** can be secured to the hull with one or more straps (not shown) or by other conventionally known fasteners.

FIGS. **5**A and **5**B show two parallel spaced cutter guides **110** on the front face **102** of UUV **100**. The cutter guides **110** are spaced apart just enough for the cutter arm **210** to pass in between the guides **110**, as shown in FIG. **7**D. When the UUV **100** encounters a fishing net or other object, its forward end **101** may become entangled in the net and cause the net to contact the two guides **110**. The cutter guides **110** prevent the net from contacting the front face **102** as the UUV **100** continues to move forward and the net is tightly stretched across the cutter guides **110**. The inventors have discovered that keeping the net away from the front face **102** of the UUV **100** ensures that the cutter arm **210** can cut through the net quickly. In accordance with an advantageous feature of the disclosed embodiment, the cutter guides **110** are acoustically transparent so they will not interfere with UUV frontal sensors and equipment, such as, the Forward Looking Sonar (FLS), retrieval hardware, among others. It will be appreciated by those skilled in the art that variations on the cutter guides **110** can include various shapes allowing for easier cutting through the object. Additional cutter guides may be placed on the top and bottom surfaces of UUV **100** to allow for the placement of UUV systems such as automatic docking systems. Alternatively, a slit opening (not shown) can be formed in the front face **102** of the UUV **100**. The slit opening provides a recessed space for the cutter arm **210** as it cuts through the fishing net or other object.

In accordance with another advantageous feature of the disclosed embodiment, the only modifications to UUV **100** required is a power connection from the UUV **100** to the linear cutting assembly **200** and the installation of control software in the memory module of the UUV **100** to be executed by the onboard control processor. The power connection from the UUV **100** to the linear cutting assembly **200** can use a right angle watertight bulkhead connector. The control software will analyze UUV speed and propulsor data to determine if a net or object has been encountered and implement the steps shown in FIG. **6** below to control the arming, deployment and retrieval of the linear cutter arm **210**. Alternatively, it shall be appreciated that the linear cutting assembly **200** can be self-contained with its own integrated power supply, memory module and control processor for running the control software.

FIG. **6** is a flow chart of a method for penetrating through a net or object using the linear cutter assembly **200**. At step **600**, the control processor of UUV **100** receives a speed signal from UUV **100** at predetermined time intervals. It should be appreciated by those skilled in the art that the speed signal can be generated by UUV **100** using any known method of speed detection. Speed sensors such as a pressure switch or a paddle wheel can be used to measure the speed at which UUV **100** is traveling.

According to one embodiment, UUV **100** is configured to travel at 3.0 knots when carrying out a mission. In this embodiment, an arming threshold speed can be set at any speed between 0 and 3 knots, preferably 2.5 knots, for the purpose of determining when to arm the linear cutting assembly **200**. Upon receiving a speed signal from UUV **100**, at step **610**, the control processor determines whether UUV **100** is traveling at a speed above the arming threshold speed. Linear cutting assembly **200** remains disarmed until the UUV **100** reaches the arming threshold speed of 2.5 knots. If the speed signal value is above the aiming threshold speed, the control processor sends a control signal to arm the linear cutting assembly **200** at step **620**, if it is not already armed. FIG. **7**A illustrates the linear cutting assembly **200** in an armed state with the linear cutter arm **210** located inside the pod **140** and at a 0 degree angle with respect to the length of UUV **100**. The method returns to step **600** to wait for the next speed signal from the UUV **100**. It should also be appreciated that other methods besides speed detection can be used to determine when to arm the UUV **100**. For example, the linear cutting assembly **200** can remain disarmed until the UUV **100** reaches a predetermined depth, such as 10 feet underwater. A pressure sensing switch or other devices and methods can be used to detect the depth of the UUV **100**. Furthermore, other embodiments can show different speed thresholds as well as travel speeds for the UUV.

A cutting activation threshold speed can be set for the purpose of determining when to deploy the linear cutting assembly **200**. It should be appreciated by those skilled in the art that UUV **100** can employ any known method of object detection. The same speed sensor used by UUV **100** to measure its speed can also be used for object detection. For instance, when UUV **100** comes into contact with an obstruction, its speed will decrease. Speed changes can be measured and provided to the control processor at predetermined time intervals such as, for example, every 5 seconds. At step **630**, the control processor determines whether UUV **100** is traveling at a speed below the cutting activation threshold speed of 2.0 knots, for example.

If UUV **100** is traveling at a speed below the cutting activation threshold speed, the control processor determines whether the linear cutting assembly **200** is armed at step **635**. The control processor sends a control signal to deploy the linear cutter arm **210** at step **640** if the linear cutting assembly **200** is armed and power is delivered to the motor **250** (FIG. **2**) of the linear cutting assembly **200**. While speed detection is one way of indirectly detecting an object obstructing the path of the UUV **100**, it should also be appreciated that other methods and devices such as, for example, a contact switch or a high frequency sonar can be used for object detection.

When actuated, the cutter arm **210** emerges from the pod **140** and pivots forward in an arc as shown in FIG. **7**B. At the same time, the moveable blade **310** starts oscillating across the stationary blade **300**. The moveable blade **310** is preferably oscillating at full cutting speed by the time the linear cutter arm **210** is at a 135 degree angle with respect to the length of the UUV **100** as shown in FIG. **7**C. In this disclosed embodiment, the moveable blade **310** has a full cutting speed of preferably 10 Hz. The cutting speed can vary depending on the type of net **750** or object encountered.

At step **650**, the linear cutting assembly **200** continues to move through its arc path and penetrates the fishing net **750** or object using the shearing action caused by the reciprocating teeth **340** and **350** (FIG. **3**). FIG. **7**D shows the linear cutter arm **210** at a 270 degree angle with respect to the longitude of the UUV **100**. The present inventors have discovered that holding the net **750** or other object away from the front face **102** of the UUV **100** by the cutter guides **110** facilitates quicker and easier cutting of the net **750**. The moveable blade **310** moves continuously back and forth at full cutting speed for a predetermined length of time, preferably 4-8 seconds depending on the type of net encountered. Alternatively, the offset cam **400** (FIG. **4**A) that causes the moveable blade **310** to oscillate back and forth may rotate for a predetermined number of revolutions or according to another suitable parameter specified by the control software.

The linear cutter arm **210** returns back to its docked position inside the pod **140** at step **660** (as shown in FIG. **7**A) and the method returns to step **600** to wait for the next speed signal from the UUV **100**. UUV **100** continues with its mission after passing through net **750**.

The length of time that the moveable blade **310** is oscillating at full cutting speed at step **650** may not be sufficient for UUV **100** to penetrate net **750** in one cutting sequence. When the next speed signal at step **600** indicates that UUV **100** is still traveling below the threshold speed at step **610** and below the cutting activation threshold speed at step **630**, the linear cutter arm **210** will be deployed again at step **640**. The linear cutting assembly **200** will repeatedly deploy the linear cutter **210** until the UUV **100** penetrates through the net **750** and resumes traveling at a speed above the cutting activation threshold speed. Optionally, the control software can set a maximum number of deployments for a given time period.

In this embodiment, the pod **140** is attached to the top, forward end **101** of the UUV **100** such that the linear cutter arm **210** will cut a vertical slit through the net **750** or object when the cutter arm **210** pivots along an arc up to 270 degrees. The size of the vertical slit is based on the length of the linear cutting arm **210** and can be increased by extending the length of the linear cutting arm **210**. As shown in FIG. **7**D, the length of the linear cutter arm **210** is preferably long enough for it to extend the entire diameter of UUV **100**. Instead of cutting a vertical slit, other slit directions can be cut by attaching the pod **140** to UUV **100** at other positions outside the hull. Optionally, multiple pods **140** can be attached around the outside of UUV **100** for cutting multiple slits. In addition, although the linear cutting arm **210** has been described as moving 270 degrees in an arc, the range of movement can vary, however, from approximately 225 degrees to 290 degrees, based on user preferences.

The foregoing merely illustrates the principles of the linear cutting assembly. It will thus be appreciated that those skilled in the art will be able to devise numerous alternative arrangements that, while not shown or described herein, embody the principles of the invention and thus are within its spirit and scope. For example, the linear cutting assembly can use a crankshaft system, instead of a cam assembly as shown in the illustrative embodiments, to transform the rotational motion from a motor into the reciprocating linear motion of a blade. In addition, those skilled in the art will be able to scale the pod and linear cutting assembly to enable them to be used on a variety of other classes of UUVs and other underwater vehicles, marine vessels, and non-marine systems. For example, although the illustrative embodiments of the pod and linear cutting assembly are described for use on UUVs having an approximate diameter of 12.75 inches, the embodiments may be linearly scaled to work with UUVs ranging in size from the 7.5 inch diameter man-portable up to the heavy weight 21 inch diameter UUV class. And, it is possible for alternative embodiments to attach more than one pod to provide extra clearance for marine vessels and underwater vehicles with unusually large protrusions or diameters.

The disclosed embodiments of the linear cutting assembly described above may not be ideal for Large diameter Unmanned Underwater Vehicles (LUUVs) that require a much larger hole to be cut in a quick and efficient manner. The problem of penetrating through nets and other objects by LUUVs is solved by cutting the object using a combination cutting module. The combination cutting module includes multiple linear cutting assemblies and a concentric cutting assembly such as described in U.S. patent application Ser. No. 12/497,285, filed on Jul. 2, 2009, entitled "Concentric Cutting Assembly, Concentric Cutting System, and Net Penetration Method," the subject matter of which is incorporated in its entirety by reference herein. The concentric cutting assembly cuts the object using a rotatable cutter with floating teeth that rotates concentrically about a non-rotatable cutter with fixed teeth. The combined severing actions of the multiple linear cutting assemblies and the concentric cutting assembly will cut a sufficiently large opening in the object to allow a LUUV to pass through.

FIG. **8** shows a Large diameter Unmanned Underwater Vehicle (LUUV) system **800** in accordance with an embodiment described herein. The LUUV **800** may have a 50 inch diameter and a square shaped front face **802** with rounded corners **804**. LUUV **800** is integrated with a concentric cutting assembly **950** at the forward end **801** and a propulsor **810** at the aft end **803**. Installed in each of the four corners **804** of LUUV **800** is a linear cutting assembly **900** similar to linear cutting assembly **200**. FIG. **9** illustrates the positions of the concentric cutting assembly **950** and four linear cutting assemblies **900** inside the LUUV **800**. The differences between linear cutting assemblies **900** and **200** are explained below.

Linear cutting assembly **900** is not housed in a housing structure such as the pod **140**. As shown in FIG. **9**, there is sufficient space for a linear cutting assembly **900** inside each corner **804** of LUUV **800**. Attached to the base plate **990** of linear cutting assembly **900** are sidewalls **980** that fasten to the inside of the hull **970**. At each rounded corner **804** of front face **802** is a long slit **940** through which a linear cutter arm **910** emerges from within the hull **970** of LUUV **800**. The length of the linear cutter arm **910** and the length and the start and end points of the slit **940** will vary depending on the range of motion desired for the linear cutter arm **910**. Similar to the motion of linear cutter arm **210**, the linear cutter arm **910** preferably moves in an arc of at least 225 degrees about a pivot point in the linear cutting assembly **900**.

Cutting assemblies **900** and **950** require a power source and a net detection signal (which can be indirectly inferred from a speed signal as described above) to operate. Both the power source and the net detection signal can be supplied by or be provided completely independent of LUUV **800**. Under the main pressure vessel **920** of LUUV **800** is a modular payload bay **930** storing sensors, a control processor for controlling the LUUV **800** and the cutting assemblies **900** and **950**, a memory for storing control software and an I/O processor. The control processor is the main processor for LUUV **800** and will run the control software for the cutting assemblies **900** and **950**. It shall be appreciated that the modular payload bay **930** can be located anywhere in the LUUV **800**, including inside the main pressure vessel **920**.

FIG. **10** is an internal view showing the components of the concentric cutting assembly **950** in accordance with the embodiment depicted in FIGS. **8** and **9**. Concentric cutting assembly **950** includes two concentric cutters: non-rotatable cutter **1080** and rotatable cutter **1090**. The forward end **801** of LUUV **800** has a 50 inch wide square front face **802** and can accommodate a non-rotatable cutter **1080** having a diameter up to 50 inches. Non-rotatable cutter **1080** comprises outer cylinder **1010** and fixed teeth **1040**. Rotatable cutter **1090** comprises inner cylinder **1020** and floating teeth **1050**.

Slide rails **1200** are attached to the inside of LUUV housing **970** as shown in FIG. **10**. Concentric cutters **1080** and **1090** move back and forth along slide rails **1200**. Concentric cutters **1080** and **1090** move forward along slide rails **1200** to engage and cut fishing nets and other objects encountered by LUUV **800** during a mission. After the object is cut, concentric cutters **1080** and **1090** retract along slide rails **1200** into their original position inside UUV housing **970**. Three slide rails **1200** are used in the example embodiment of FIG. **10**. If desired, particular embodiments may optionally include only two slide rails, more than three slide rails, or any other means for extending and retracting concentric cutters **1080** and **1090**. Those skilled in the art will appreciate that alternative embodiments may employ roller bearings instead of slide rails. The roller bearings can be contained within slots to prevent rotation of non-rotatable cutter **1080**.

Outer cylinder **1010** is mounted on slide rails **1200**. Inner cylinder **1020** rotates concentrically within outer cylinder **1010**. Six bearing plates **1030** are mounted to outer cylinder **1010** (four of which are visible in FIG. **10**). Bearing plates **1030** serve two main purposes: (1) to keep concentric cylinders **1010** and **1020** axially aligned and (2) to keep the floating teeth **1050** in constant contact with the fixed teeth **1040**. Each bearing plate **1030** can be adjusted in depth and tilt. If desired, particular embodiments may optionally mount bearing plates **1030** to inner cylinder **1020**. Any desired number of bearing plates may optionally be used, however, the present inventors have found that six bearing plates are effective in axially aligning concentric cylinders **1010** and **1020**.

Concentric cylinders **1010** and **1020** of the disclosed embodiment are made of carbon fiber. However, cylinders **1010** and **1020** can be made of any other material with properties similar to carbon fiber, such as, for example, titanium, stainless steel and carbon steel. The present inventors have found that carbon fiber is sufficiently strong to be used for penetrating nets and other objects and can be easily fabricated.

As shown in FIG. **10**, outer cylinder **1010** can be formed with fixed teeth **1040** protruding from one end in a direction parallel to the center axis of outer cylinder **1010**. Fixed teeth **1040** are each formed as blades having substantially the same angled cutting edge as each other. According to the embodiment of FIG. **10**, one hundred fifty fixed teeth **1040** are evenly spaced about outer cylinder **1010**. A cutting assembly embodying the principles of the invention can have any desired number of fixed teeth, however. Moreover, the fixed teeth can each have different shapes than shown, as is known in the art.

In accordance with an advantageous feature of the disclosed embodiment, three floating teeth **1050** are spring-mounted about one end of the outer surface of inner cylinder **1020**, although any number of floating teeth **1050** can be spring-mounted. Similar to fixed teeth **1040**, floating teeth **1050** are formed as blades and have substantially the same angled cutting edge as each other. Further, floating teeth **1050** extend from inner cylinder **1020** along the same direction as fixed teeth **1040** such that the blades of floating teeth **1050** are parallel to the blades of fixed teeth **1040**.

In one embodiment, fixed teeth **1040** and floating teeth **1050** are fabricated from stainless steel. If desired, particular embodiments may optionally fabricate teeth from titanium, carbon steel, or any other metal with properties similar to stainless steel. The inventors found that galling can roughen the contact areas between fixed teeth **1040** and floating teeth **1050** after repeated use of the concentric cutting assembly **950**. A lubricant may optionally be placed between the cutting surfaces to prevent material transferring from one surface to the other surface and to reduce friction. Alternatively, a cutting surface may be coated with a hardened material such as titanium nitride (TiN), titanium aluminum nitride (TiAN) or titanium carbon nitride (TiCN) to prevent material transfer. In addition, an anti-friction coating such as molybdenum sulfite (MoST) may be optionally placed over the hardened material to reduce friction.

If LUUV **800** does not have its own neutral buoyancy mechanism, particular embodiments may optionally include foam **1060** for neutral buoyancy. Foam **1060** can be positioned in the center of inner cylinder **1020** around center pipe **1070**. If desired, foam **1060** can alternatively be positioned in the rear of concentric cutting assembly **950** if LUUV **800** has a forward looking sonar located in the center of inner cylinder **1020**.

In accordance with an advantageous feature of this disclosed embodiment, the concentric cutting assembly **950** and the multiple linear cutting assemblies **900** integrate seamlessly within LUUV housing **970**. Seamless integration of the cutting assemblies **950** and **900** has the effect of minimizing drag as LUUV **800** moves underwater.

FIG. **11** is a profile view of concentric cutting assembly **950** in accordance with the embodiment disclosed in FIG. **10**. Floating teeth **1050** are mounted to inner cylinder **1020** using low profile springs **1100**. Wavy springs can be used to keep the cutting assembly profile narrow. The inventors have found that mounting floating teeth **1050** to inner cylinder **1020** using springs **1100** provide three main benefits. First, springs **1100** keep the cutting surfaces formed by floating teeth **1050** and fixed teeth **1040** tightly together. Tight cutting surfaces facilitate quick and efficient cutting of nets and other objects. Second, springs **1100** keep cylinders **1010** and **1020** tightly against each other. Third, spring-mounted floating teeth **1050** act like another set of bearings to keep concentric cylinders **1010** and **1020** evenly apart and axially aligned.

It will be appreciated that the size and shape of floating teeth **1050** and fixed teeth **1040** are not limited to the examples depicted in FIGS. **10** and **11**. In fact, any size and shape of floating teeth **1050** and fixed teeth **1040** can be used so long as each floating tooth **1050** creates a shearing action when sliding against fixed teeth **1040**. Preferably, the blades of fixed teeth **1040** have the same or substantially the same cutting angle. The present inventors have found that blades with a 30 to 70 degree angle, preferably a 55 degree angle, are effective at cutting nets and other objects. It will be appreciated that the cutting angle may need to be adjusted based on the objects to be penetrated and can be changed to any angle desired. For instance, blades with wide cutting angles are more effective at cutting through thick fishing nets than blades with narrower cutting angles. Moreover, the shearing action is more effective if the cutting surface consists of the entire edge of the blade. The present inventors have also discovered that fixed teeth **1040** with rounded tips have the advantageous features of capturing and holding the net in place while also preventing the rounded tips from catching on the net itself as rotatable cutter **1090** rotates to cut the object. In contrast, floating teeth **1050** preferably have pointed tips for more effective cutting.

Another advantageous feature of the disclosed embodiment is that rotatable cutter **1090** is free floating—supported only by means that keep it axially aligned with non-rotatable cutter **1080**. In the example embodiment depicted in FIGS. **10** and **11**, non-rotatable cutter **1080** is cylindrical, however, it will be appreciated that rotatable cutter **1090** may be shaped other than as a cylinder. If desired, particular embodiments may optionally include a rotatable cutter shaped as an equilateral triangle, square, Y-shaped, pentagon, or any other shape so long as the rotatable cutter can rotate concentrically within non-rotatable cutter **1080** and be mounted with at least one floating tooth.

If desired, non-rotatable cutter **1080** can have a non-cylindrical shape in systems in which the non-rotatable cutter does not have to conform to the shape of the LUUV system **800**. In an alternative embodiment, for example, the concentric cutters can be comprised of two concentric equilateral triangles in which one, two, or three floating teeth are mounted to a respective corner of the rotatable triangular cutter, and bearing plates are aligned with the floating teeth for axially aligning the concentric cutters. It will be appreciated by those skilled in the art that a rotatable cutter embodying the principles of the invention can be any shape as long as it can rotate concentrically about a non-rotatable cutter and has floating teeth that are kept tightly against fixed teeth attached to the non-rotatable cutter.

Rotatable cutter **1090** can rotate clockwise or counter clockwise continuously or intermittently in one direction. Those skilled in the art will appreciate that the direction of rotation does not matter as long as floating teeth **1050** slide against fixed teeth **1040** to create a shearing action that cuts fishing nets and other objects. In an alternative embodiment, rotatable cutter **1090** can be configured to rotate continuously or intermittently in both directions. For instance, rotatable cutter **1090** can alternate rotating clockwise and counter clockwise for a pre-determined time period.

FIG. **12** shows an inside view of concentric cutting assembly **950** in accordance with an embodiment described herein. A motor system housed within motor housing **1230** provides the means to rotate inner cylinder **1020**. The motor system may be a brushed motor equipped with a planetary gearhead. By mounting motor housing **1230** to outer cylinder **1010**, rotatable cutter **1090** can start rotating at any position with respect to non-rotatable cutter **1080** and gain momentum before concentric cutting assembly **950** contacts an object. Spur gear **1220** is mounted to the output shaft of the planetary gearhead and mates with internal ring gear **1210**, which is mounted to inner cylinder **1020**. If desired, particular embodiments may optionally include multiple motors instead of a single motor mounted radially about the outer cylinder **1010**.

Actuator **1240** moves concentric cutters **1080** and **1090** forward through LUUV housing **970** to penetrate nets and other objects and retracts concentric cutters **1080** and **1090** after penetration. Actuator **1240** may have a stroke length of 3" and can move from fully retracted to fully extended in 1.5 seconds and provide up to 50 lbs of actuation force to outer cylinder **1010**. One contact point of actuator **1240** is mounted to outer cylinder **1010** while the other contact point of actuator **1240** is mounted on the inside of LUUV housing **970** as shown in FIG. **12**. If desired, particular embodiments may optionally include multiple actuators without significantly increasing the profile or thickness of concentric cutting assembly **950**. The multiple actuators can be placed radially about outer cylinder **1010** and LUUV housing **970**.

FIG. **13** is a schematic diagram of an electronic assembly of concentric cutting assembly **950** in accordance with an embodiment described herein. Power is required to run the electronics housed in electronics housing **1500**. Concentric cutting assembly **950** can be configured to utilize the battery typically used by the power propulsor **810** of the LUUV **800** to power its own electronics. Electronics housing **1500** contains microcontroller **1530**, DC-DC converter **1510**, motor relay **1520** and actuator controller **1540**. As shown in FIGS. **9** and **10**, LUUV housing **970** has a recess at the rear of concentric cutting assembly **950**. This recess is deep enough to fit electronics housing **1500**.

Microcontroller **1530** receives signals from the control processor of LUUV **800** to control concentric cutting assembly **950** functions including setting a cutter deployment speed for the speed at which concentric cutters **1080** and **1090** are deployed, a cutter run time for the length of time that rotatable cutter **1090** rotates at full speed, and a cutter retrieval time for the length of time it takes to retract concentric cutters **1080** and **1090** after cutting.

Preferably, components such as motor housing **1230**, actuator **1240** (FIG. **12**) and electronics housing **1500** are made waterproof. In this disclosed embodiment, actuator **1240** is waterproofed using a silicone rubber boot. Further, motor housing **1230** is machined from PVC with a double "O" ring shaft seal. All housing joints are double sealed to protect against water infiltration. Surrounding electronics housing **1500** are four waterproof connectors **1550**. One waterproof connector is located on each side of electronics housing **1500**.

FIG. **14** is a flow chart of a method for penetrating through a fishing net using the combined cutting assemblies **900** and **950** of LUUV **800**. At step **1400**, the control processor of LUUV **800** waits for a speed signal from LUUV **800**. It should be appreciated by those skilled in the art that the speed signal can be generated by LUUV **800** using any known method of speed detection such as those described above in connection with FIG. **6**.

According to one embodiment, LUUV **800** is configured to travel at 5.0 knots when carrying out a mission. An arming threshold speed can be set at any speed between 0 and 5 knots, preferably 3.5 knots, for the purpose of determining when to arm the cutting assemblies **900** and **950**. Upon receiving a speed signal from LUUV **800**, the control processor determines at step **1410** whether LUUV **800** is traveling at a speed above the arming threshold speed. The cutting assemblies **900** and **950** remain disarmed until LUUV **800** reaches the arming threshold speed of 3.5 knots. If the speed signal value is above the arming threshold speed, at step **1420**, the control processor of LUUV **800** sends a control signal to arm the linear cutting assemblies **900** and sends a control signal to microcontroller **1530** to arm concentric cutting assembly **950**, if they are not already armed. FIG. **15**A illustrates the cutting assemblies **900** and **950** in an armed state. The concentric cutters **1080** and **1090** (FIG. **10**) and linear cutter arms **910** (FIG. **9**) are inside LUUV housing **970** (FIG. **9**) when the cutting assemblies **900** and **950** are in the armed state. The method returns to step **1400** to wait for the next speed signal from LUUV **800**. It should be appreciated by those skilled in the art that LUUV **800** can employ other methods to determine when to arm the linear cutting assemblies **900** and **950**.

The same speed sensor used by LUUV **800** to measure its speed can also be used for object detection. For instance, when LUUV **800** comes into contact with an obstruction, its speed will decrease. Speed changes can be measured and provided to the control processor and microcontroller **1530** at predetermined time intervals, such as, every five seconds. A cutting activation threshold speed can be set for the purpose of determining when to deploy the cutting assemblies **900** and **950**. It should be appreciated by those skilled in the art that LUUV **800** can employ any known method of object detection.

At step **1430**, the control processor of LUUV **800** determines whether LUUV **800** is traveling at a speed below the cutting activation threshold speed of 3.0 knots. If LUUV **800** is traveling at a speed below the cutting activation threshold speed, the control processor determines whether the cutting assemblies **900** and **950** are armed at step **1435**. The control processor sends a control signal to deploy the linear cutter arms **910** and sends a control signal to microcontroller **1530** to simultaneously deploy concentric cutters **1080** and **1090** at step **1440** if the cutting assemblies **900** and **950** are armed.

During deployment, concentric cutters **1080** and **1090** extend out of the forward end **801** of LUUV **800** as shown in FIG. **15**B along slide rails **1200** (FIG. **10**). At the same time, rotatable cutter **1090** starts rotating, preferably in a counter clockwise direction. Rotatable cutter **1090** is also preferably rotating at full cutting speed by the time non-rotatable cutter **1080** comes into contact with fishing net **750**. In this disclosed embodiment, rotatable cutter **1090** has a full cutting speed of 100 revolutions per minute (RPM). When the four linear cutter arms **910** are simultaneously actuated, the cutter arms **910** emerge from the LUUV **800** through the respective slits **940** as shown in FIG. **15**B and pivot forward in an arc as shown in FIG. **15**C. At about the same time, the moveable blades of the linear cutter arms **910** start oscillating across the respective stationary blades of the linear cutter arms **910**. The moveable blades of the linear cutter arms **910** are preferably oscillating at full cutting speed by the time the linear cutter arms **910** are at a 90 degree angle with respect to the length of the LUUV **800** as shown in FIG. **15**C. In this disclosed embodiment, the moveable blades of the linear cutter arms **910** have a full cutting speed of preferably 10 Hz. The cutting speed can vary depending on the type of net **750** or object encountered.

Instead of simultaneously deploying the cutting assemblies **900** and **950**, it will be appreciated by those skilled in the art that the control processor of LUUV **800** can send a control signal to deploy the linear cutter arms **910** simultaneously at step **1440** after a predetermined time period such as, for example, fifteen seconds after deploying the concentric cutters **1080** and **1090**. Alternatively, the control software for LUUV **800** can automatically add a predetermined time delay between the deployment of each pair of linear cutting assemblies **900**. For example, at step **640**, the control software for LUUV **800** may deploy two opposing linear cutter arms **910** and then wait 10 seconds before deploying the other two opposing linear cutter arms **910**.

At step **1450**, the LUUV **800** penetrates through fishing net **750**. The net **750** first encounters the concentric cutters **1080** and **1090**. Non-rotatable cutter **1080** of the concentric cutting assembly **950** captures and holds net **750** using at least one of the fixed teeth **1040**. The present inventors have discovered that holding the net **750** or other object in place using non-rotatable cutter **1080** has two primary benefits. First, LUUV **800** is held still with respect to net **750**. In other words, rotatable cutter **1090** will not cause LUUV **800** to rotate. Second, net **750** is held taut which facilitates quicker and easier cutting. Rotatable cutter **1090** rotates for a predetermined length of time, preferably 6 seconds. The length of time should be sufficient for LUUV **800** to cut a circular hole **1600** as shown in FIG. **16** using the shearing action caused by floating teeth **1050** sliding against fixed teeth **1040**. It will be appreciated that the direction of rotation can be clockwise or counter clockwise so long as a shearing action results from the rotation.

The net **750** then stretches slightly, pulling back over the square front face **802** of LUUV **800** until it encounters the four linear cutter arms **910**. As the linear cutter arms **910** swing forward in an arc, they cut linear slits **1610** in the net **750** as shown in FIG. **16**. The moveable blades of the linear cutter arms **910** rotate continuously at full cutting speed for a predetermined length of time, preferably 8 seconds. Alternatively, the moveable blades of the linear cutter arms **910** may rotate for a predetermined number of revolutions or according to another suitable parameter specified by the control software. The cuts made by the linear cutter arms **910** and the concentric cutters **1080** and **1090** intersect **1620** as shown in FIG. **16**. As the LUUV **800** passes through the net **750**, the net **750** folds back along the cut slits **1610**.

LUUV **800** continues with its mission after cutting the net **750**. The linear cutter arms **910** swing backward in an arc to their starting positions inside the hull **970**. The concentric cutters **1080** and **1090** retract inside the hull **970** along slide rails **1200** of LUUV **800**. The method returns to step **1400** to wait for the next speed signal from the LUUV **800**.

The length of time that the moveable blades of the linear cutter arms **910** are oscillating at full cutting speed may not be sufficient for LUUV **800** to penetrate net **750** in one cutting sequence. When the next speed signal at step **1400** indicates that LUUV **800** is still traveling below the arming threshold speed at step **1410** and below the cutting activation threshold speed at step **1430**, the cutting assemblies **900** and

950 will be deployed again. The cutting assemblies **900** and **950** will repeatedly deploy the linear cutter arms **910** and concentric cutters **1080** and **1090**, respectively, until the LUUV **800** penetrates through the net **750** and resumes traveling at a speed above the cutting activation threshold speed.

Alternatively, at step **1435**, the control processor of LUUV **800** can additionally determine if the cutting sequence has repeated for a predetermined number of times within a predetermined period of time. If not, the cutting assemblies **900** and **950** may be deployed at step **1440**. Otherwise, an error signal is recorded in the memory and communicated to an external device via a wireless communications link, for example. The control processor can wait a predetermined period of time before returning to step **1400**.

Disclosed embodiments will simplify and add flexibility to UUV and LUUV mission planning and execution. UUV operation remains essentially unchanged until an object is detected. Once the object is detected, the concentric cutting assembly will engage the object, penetrate the object, and allow the UUV to carry out its mission with minimal loss of time. Disclosed embodiments allow a greater percentage of missions to be performed with a reduced risk of UUV loss or damage.

The foregoing merely illustrate the principles of the invention. For example, although the concentric cutters of the illustrative embodiments consist of a single non-rotatable cutter and a single rotatable cutter, it is possible for alternative embodiments to incorporate more than one stationary cutter and more than one rotating cutter. In addition, although the floating teeth and the linear cutting teeth of the illustrative embodiment have a certain shape, other shapes, materials and configurations are possible. Although the LUUV described above has a square shaped front face with rounded corners, it will be appreciated by those skilled in the art that the LUUV can have other shapes. For example, the LUUV can be round shaped, in which case, the linear cutting assemblies would be placed outside the LUUV in streamlined pods similar to pod **140** shown in FIG. **1**.

Although the invention may be used to particular advantage in the context of LUUVs, those skilled in the art will be able to incorporate the invention into other underwater vehicles and marine vessels. Those skilled in the art will be able to incorporate the invention into non-marine systems such as, for example, unmanned land vehicles (e.g., cut through vegetation and barbed wires), unmanned robots and other remote vehicles (e.g., space applications). It will thus be appreciated that those skilled in the art will be able to devise numerous alternative arrangements that, while not shown or described herein, embody the principles of the invention and thus are within its spirit and scope.

What is claimed as new and desired to be protected by Letters Patent of the United States is:

1. A cutting apparatus comprising:

a cutter arm comprising a first blade and a second blade;

a motor directly linked to a rotatable drive shaft and configured to move the rotatable drive shaft and further configured to move the second blade linearly back and forth and parallel to the first blade, wherein the cutter arm is configured to rotate about the rotatable drive shaft and a pivot point of rotation of the cutter arm is coaxial with the rotatable drive shaft, wherein the second blade comprises an engaging end, the engaging end includes perimeter within the engaging end defining a drive shaft receiving hole, and the drive shaft is within the drive shaft receiving hole and traversing a plane encompassing the perimeter.

2. The cutting apparatus of claim **1**, wherein the cutter arm is configured to rotate at least 225 degrees.

3. The cutting apparatus of claim **1**, wherein the motor is further configured to drive the rotation about the drive shaft.

4. The cutting apparatus of claim **1**, wherein the motor does not drive the rotation of the cutter arm.

5. The cutting apparatus of claim **1**, wherein linear motion of the second blade and the rotation of the cutter arm are driven independently.

6. The cutting apparatus of claim **1**, wherein the second blade is configured to move linearly back and forth when the cutter arm is positioned at more than one angle of rotation about the drive shaft.

7. The cutting apparatus of claim **1**, wherein the motor is directly linked to the rotatable drive shaft through at least one mechanical connection.

8. The cutting apparatus of claim **7**, wherein the at least one mechanical connection includes a gear.

9. The cutting apparatus of claim **8**, wherein the gear is a bevel gear.

10. The cutting apparatus of claim **8**, wherein the at least one mechanical connection further includes a second gear and the first and second gears are configured to transfer mechanical energy from the first gear to the second gear.

11. The cutting apparatus of claim **1**, further comprising an elongated opening on a surface of a housing structure, wherein the cutter arm is configured to rotate out of the housing structure.

12. The cutting apparatus of claim **11**, wherein the housing structure is a cutting apparatus housing structure configured to connect to a hull of the underwater vehicle.

13. The cutting apparatus of claim **11**, wherein the housing structure is the hull of an underwater vehicle.

14. The cutting apparatus of claim **1**, further comprising a clutch assembly connected between the motor and the cutter arm.

15. The cutting apparatus of claim **14**, wherein the clutch assembly is configured to slip when the cutter arm encounters resistance while rotating.

16. The cutting apparatus of claim **14**, wherein the clutch assembly comprises a spring that pushes a clutch plate to control rotation of the cutter arm.

17. The cutting apparatus of claim **14**, wherein the cutter arm is configured to rotate at least **225** degrees.

18. The cutting apparatus of claim **14**, further comprising a drive shaft in mechanical association with the motor, wherein the second blade is configured to move linearly back and forth when the cutter arm is positioned at more than one angle of rotation about the drive shaft.

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